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TALES FROM THE ARCHITECT

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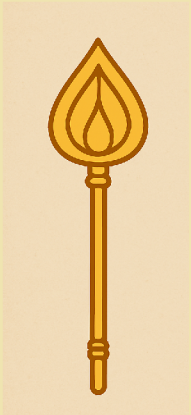
Wrath of Time



Tales from the Architect: The Wrath of Time

Tejaswi P Ramesh

August 2025

Contents

1 Time, Perception and Continuity of linear time **4**
- 1.1 The Purpose of Conscious intent . . . 4
- 1.2 The Trajectory . . . 5
- 1.3 Discretizing the perception based on time distribution . . . 6
- 1.4 Family circles . . . 6
- 1.5 Types of intents . . . 6
- 1.6 Further Discretizations based on time distribution . . . 7
- 1.7 Defining Continuous Linear time through Observation . . . 8

2 Continuity of Perception and intents **9**
- 2.1 Energy Distribution . . . 9
- 2.2 Observing and plotting the trajectory . . . 9
- 2.3 Creation of target state trajectories . . . 10
- 2.4 Targeting the conscious intent for the location desired . . . 11
- 2.5 Continuity of location . . . 12

3 Deception and Energy for the movement **13**
- 3.1 Introducing deception in the interaction . . . 14
- 3.2 The application of conscious intent for deception . . . 16
- 3.3 The continuity of the deception . . . 16

4 Linear time and the origin of the multiverse **18**
- 4.1 The Mechanics of hierarchical transition states . . . 18
- 4.2 Creation of Observers . . . 18
- 4.3 The Transition states . . . 20
- 4.4 The correlation to linear time . . . 20

5 Interaction of the observers **22**
- 5.1 Movement drag between transition states . . . 22
  - 5.1.1 Movement drag metrics . . . 23
  - 5.1.2 Observer conflict Illustration . . . 23
  - 5.1.3 Resolution of the transition states . . . 24

6 The interaction of the prime observer **26**
6.1 Creating new locations from " X " 26
6.2 Creation of locations and continuity 26
6.3 The Prime observer 27
6.4 Creation of observers 28
6.5 Creation of Masculine primes 29
6.6 The sequence of Masculine primes 30

7 The Aligned and the mis-aligned observers **31**
7.1 The iterative process of interaction in the transition 32
7.1.1 The Aligned Observers 32
7.2 The Stochastic transitions 33
7.2.1 Creation of other observers 34
7.3 The Mis-aligned observers 34

8 Time reversibility of geometric observers **36**
8.1 Defining the transition states through the three dimensional image 36
8.2 Interaction of the observers with attention vectors 37
8.3 Altering the attention vector of the interacting observers through perception 38
8.4 Initial Alignment of the masculine observer with the interacting observer 39
8.5 Identifying the current moment of the interacting observer 40
8.5.1 Identifying the current moment or the present in the time spectrum 41
8.6 Engineering the trajectories by the masculine observers 41
8.6.1 Predicting and engineering the diversion of the attention vector 42
8.7 Engineering the attention vector to create perception 42
8.8 Time independence of programming intents 43

9 Perception of movement **45**
9.1 Defining the timeline as a the transient time flow between the transition states 45
9.2 Defining Perception 45
9.3 Geometric narrative 46
9.4 True Illusions 46
9.4.1 The Point Universe 47
9.5 Deceptive illusions 48

10 The Geometric Consciousness **50**
10.1 The geometric manipulation of movement nodes 50
10.2 The geometric copy of the consciousness 51

11 Engineering Time-flow **53**
11.1 Visualizing the source of energy for such purpose based interactions 55

12 Defining Consciousness as a location awareness mechanism **58**
12.1 Trajectory plotting of the fifth dimensional awareness through their attention . . . 62
12.1.1 Types of consciousness . . . 63
12.1.2 Fifth dimension perspective - Experiencing time in discrete form . . . 64
12.2 Continuity of the location . . . 65
12.2.1 The backwards in time observation of the discrete fifth dimensional perspective . . . 66

13 The geometric observers **68**
13.1 Outside the Location boundary X . . . 68
13.2 The location boundary X . . . 69
13.3 Tracking other observers . . . 70

14 Geometric Current moment **72**
14.1 The mechanism of projected intents . . . 73
14.2 Application of deception . . . 74
14.3 Differential equations and locations . . . 74

15 Timeline Mapping **76**
15.1 The timeline . . . 76
15.2 Factoring the overall population . . . 77
15.3 Factorization of the timeline . . . 77
15.4 Correlating an individual's timeline with other timelines . . . 78
15.4.1 Sorting the above interactions . . . 78
15.5 The Strategy . . . 79

16 The geometric observation of energy **81**
16.1 Energy . . . 82
16.1.1 Correlation of the above information with geometry . . . 82

17 Tracing the energy trail of the masculine **86**
17.1 The State of the individual A in the location X . . . 88

18 Relative Linearity of Time **91**
18.1 Changing the perception from first perspective to the third perspective . . . 94
18.1.1 The Observer linearity of Time . . . 94
18.2 Altering the State of Observation . . . 96
18.2.1 The Change of States . . . 96
18.2.2 The correlation to Energy . . . 97
18.2.3 The mechanics of the state change . . . 98
18.2.4 The unobserved time and the geometric back-flow effect . 98

1 Time, Perception and Continuity of linear time

Let there be an individual " A " whose lifetime in a location " X " is given by the duration of T units of time.

Let there be " P " conscious intents for individual A where each conscious intent is an accumulation of conscious intents with continuity that comes from the family tree and territory tree of individual A.

1.1 The Purpose of Conscious intent

The conscious intents is assumed to be a set of interaction keys that describe his interaction with other conscious intents in the surroundings. It is a boundary condition for the perception which allows the individual to observe specific kinds of relative movement in the surroundings and interact with the conscious intent such that it could have one of the following effect :

1. No effect (The interaction has no specific purpose) on the interaction keys in the surroundings

2. Alter the interaction keys in the surroundings

3. Remove the interaction keys in the surroundings

Therefore the interaction keys could therefore be identified as conscious intents that is programmed or designed to react or respond when it identifies another interaction key that is identified in the surroundings.

The lifetime of Individual A has continuity starting from the prime observer to his generation of creation where each iteration of lifetimes that has been created till the birth of individual A has transferred various sets of interaction keys through the family tree.

On the other hand , the birth of individual A in a location " X " has a growth cycle where individual A observes and interacts with his surroundings with interaction keys inherited from his family trees and either voluntarily or involuntarily absorbs new interaction keys or alters his existing interaction keys. Every territory (sub-location or sub-sub location) has an observing masculine who has a set of interaction keys embedded in the territory of his observation for communication of various intents.

Therefore the individual A is part of two distinct interaction keys namely his family tree and his territory tree.

1.2 The Trajectory

The trajectory of individual A in location " X " has the following form :

At t = 0

Individual A is born at a sub-location X0

Individual interacts with " k0 " individuals in the sub-location X0 for a duration = dt0

At t = t + dt0

Individual A is at a sub-location X0

Individual interacts with " k1 " individuals in the sub-location X0 for a duration = dt1

.....

The perception of time for the individual has continuity from his observation of linear time that is defined by a narrative that could be discretized by his " P " conscious intents.

Let P = P0+ P1+P2+...

Where each part P0+P1,P2,etc is a perception or a specific conscious intent that observes his surroundings and identifies the relative moment such as if interacting with an individual from the friend circle, family circle and identify the specific conscious intent from each of these individuals and respond accordingly according to the purpose of the interaction key.

When a specific interaction is introduced in an interaction of " t " units , the intent for the duration would be a copy of the behaviour pattern of the family tree or the territory tree masculine who introduced it in the perception of individual A. In some sense, his thoughts and memories could be quantum entangled to the interaction thus replicating his behaviour during the duration of " t " units.

1.3 Discretizing the perception based on time distribution

Where P includes information that describes information about his time distribution which is of the following format :

1.4 Family circles

Time spent with individual A1

Time spent with individual B1

Time spent with individual C1

Where A1,B1 and C1 is the top three individual A who choose to spend time with as part of his likes,dislikes and obligations.

Friends circles

Time spent with individual A2

Time spent with individual B2

Time spent with individual C2

Where A1,B1 and C1 is the top three individual A who choose to spend time with as part of his likes,dislikes and obligations.

Other circles

Time spent with individual A3

Time spent with individual B3

Time spent with individual C3

Where A1,A2,A3,B1,C1 etc is the top three individual A who chooses to spend time with as part of his likes,dislikes and obligations.

1.5 Types of intents

Suppose the trajectory of individual A could be isolated by various metrics such as the following :

The Location trajectory of individual A could have the following form X0,X1,...., Xn

The time distribution trajectory of individual A could have the following form dt0,dt1,....,dtn

The interaction distribution with various individuals could have the following form k0,k1,...,kn

The above distribution is therefore the superposed perception of individual A during his lifetime.

However each interaction in various locations such as :

Individual A interaction with " k0 " individuals at location X0 for a duration of dt0 units

1.6 Further Discretizations based on time distribution

dt0 = dt01 + dt02 + dt03 +....+dt0p

Where each time distribution component dt01 , dt02 etc. is used for various individual conscious intents such as P1,P2,...etc . Therefore if individual A had used all " P " interaction keys in the interaction of " dt0 " in the location X0 , then there could be " z " distinct behaviour patterns which may or may nor be contradictory. Under normal circumstances the conscious intents are expected to be in alignment with each other if the conscious intents are fully voluntary but if the conscious intents are introduced with an external application of force then the conscious intents could be contradictory to the conscious intents that individual A has adopted voluntarily.

Then during the lifetime of the individual A each of his conscious intents or perceptions could take a linear form based on the continuity of observations through various sub locations :

dt0 = dt01 + dt02 + dt03 +....+dt0p at location X0

dt1 = dt11 + dt12 + dt13 +....+dt1p at location X1

dt2 = dt21 + dt22 + dt23 +....+dt2p at location X2

.....

1.7 Defining Continuous Linear time through Observation

Isolating and redistributing the time distribution for various conscious intents throughout the locations , the time distribution could be re-classified as :

Where the time distribution for the conscious intent or perception P1 is given by

dtP0 = dt01 + dt11 + dt21+....+ dtnp where the continuity of the perception P0 flows through X1,X2,.....,Xn

dtP1 = dt02 + dt12 + dt22 + ...+ dtnp where the continuity of the perception P0 flows through X1,X2,.....,Xn

.....

Where "n" is the number of locations the interaction keys(p0,p1,...,p) flows through which could be distinct for each conscious intent or perception.

Therefore the continuity for the perception or the conscious intent that is carried by the individual A has a linear observation for the masculine who created or embedded the intent into the perception of individual A. Individual A could then form a an extension of life for the masculine consciousness that created the conscious intents.

2 Continuity of Perception and intents

Let there be N individuals in the location " X " . Let the location " X " have " n " sub-locations.

Let each individual have stored potential energy E units

Each individual is assumed to be an accumulation of P (P0 + P1 +P2+.,..) conscious intents from his family and territory tree.

2.1 Energy Distribution

Therefore each individual has a total of E units of energy for all his conscious intents P that could be further split as the following :

Conscious intent P0 has E0 units of energy

Conscious intent P1 has E1 units of energy

Conscious intent P2 has E2 units of energy

.....

Therefore E = E0 + E1 +...

Where each proportion of energy is stored for each of his conscious intents P0 , P1 , ...etc

2.2 Observing and plotting the trajectory

Suppose the trajectory of individual A could be isolated by various metrics such as the following :

The Location trajectory of individual A could have the following form X0,X1,...., Xn

The time distribution trajectory of individual A could have the following form dt0,dt1,....,dtn

The interaction distribution with various individuals could have the following form k0,k1,...,kn

Let P0 be defined as the conscious intent to define his sub-locations along his trajectory such as X1,X2 etc.

The choice of the conscious intent for the sub-location X1 could be made by observing the current location X0

Let there be " k0 " individuals in the sub-location X0 with their own trajectory that has an information set that includes the locations in their trajectories X_k, the individuals they have interacted in their trajectories k_k , the total conscious intents of each individuals (P_k = P_1+P_2+....) and the conscious intents of all the other individuals they have interacted with (P_k_k) etc

The number of sub-locations which is accessible from the location X0 could be determined by observing all the information in X_k,k_k,P_k and P_k_k . Furthermore the energy distribution for each of these conscious intents stored by each of " ko " individuals along with the energy distribution stored from every of the k_k individuals for their own conscious intents.

The accessibility of any sub-location for the trajectory of the individual is determined by observing the conscious intents from the " k0 " individuals which is stored in " P_k " and observing the conscious intents P_k_k which is stored from various other k_k individuals.

The continuity of all the information is maintained by the individual in sub-location X0 during the interaction of dt0 units with the " k0 " individuals who are then connected to k_k individuals through continuity of information, energy and mass through various other sub-locations.

Every conscious intent from associated interaction of " dt0" unit could be accessible for the individual by observation from his own collection of conscious intents (P = P1 +P1+P3+...) which are interaction keys that are specifically designed to observe relative movement and interact with it which could be used to create or divert location trajectories based on the information acquired from the interaction keys.

2.3 Creation of target state trajectories

Suppose the individual is able to observe all the conscious intents in the interaction at sub-location X0 , and then determine the desired target sub-location X1 after the interaction of dt0 units ends , then energy is diverted to observe the trajectories from his current location to the target location X1 such that there is no interference or interception from the "k0" individuals in the location X0 or all from all the associated " k_k " individuals to the interaction.

The higher the conscious awareness of the individual , the larger the amount of information from the set X_k,k_k,P_k and P_k_k from any sub-location and thus an accurate trajectory could be plotted to the desired location X1 through the law of minimal action where the best trajectory is plotted that minimizes interaction durations and energy expenditure.

Suppose if the trajectory of the individual could be interrupted by "k0" and " k_k" associated individuals, then a continuous observation of trajectories could be made thus making the trajectory plotting process location dependent. This is because if the interruption of the trajectory process is dependent on the sub-location or sub-sub location of the intercepting individuals then each state of interruption defined by their relative locations for the interruption could be used to extract more information where more available location trajectories could be observed by the newly associated k_k individuals with each shift in interruption strategies.

Therefore the process of continuous interruption of trajectories for any individual will increase his conscious awareness through continuous observation of the probable intercepting individuals and their trajectories.

2.4 Targeting the conscious intent for the location desired

Suppose the individual had a desired target location X1 based on his conscious intent P0 , then he would have an energy reserve of E0 units to observe the matching conscious intents from the " k0 " individuals and the " k_k " associated individuals through the interaction duration " dt0 " units. Since each conscious intent has a set of stored locations for its forward trajectory , the individual could observe those location and select their target sub-location to divert their energy to creating that trajectory . If the trajectory to the chosen sub-location from one of the k_k individuals is plotted in alignment with the same conscious intent then the total amount of energy diverted to the location trajectory will be higher than E0. This is because the stored energy from the aligned individual towards the same intent will be used to jointly create the trajectory towards the target sub-location.

Where the time distribution for the conscious intent or perception P1 is given by

dtP0 = dt01 + dt11 + dt21+....+ dtnp where the continuity of the perception P0 flows through X1,X2,.....,Xn

dtP1 = dt02 + dt12 + dt22 + ...+ dtnp where the continuity of the perception P0 flows through X1,X2,.....,Xn

.....

Where "n" is the number of locations the interaction keys(p0,p1,...,p) flows through which could be distinct for each conscious intent or perception.

Therefore the continuity for the perception or the conscious intent that is carried by the individual A has a linear observation for the masculine who created or embedded the intent into the perception of individual A. Individual A could then form a an extension of life for the masculine consciousness that created the conscious intents.

2.5 Continuity of location

Suppose the Location trajectory of individual A could have the following form X0,X1,...., Xn ,

The location trajectory of his conscious intent P0 could be X0,X4,X7,...., Xn where dt01 duration of time was used in sub-location X0 , dt11 duration of time was used in sub-location X4 , dt21 duration of time was in sub-location X7 etc.

Therefore the linear masculine observer of the conscious intent P0 will observe continuity through various locations which is threaded through the continuity of time.

3 Deception and Energy for the movement

Let there be N individuals in the location " X " . Let the location " X " have " n " sub-locations.

Let each individual have stored potential energy E units

Each individual is assumed to be an accumulation of P (P0 + P1 +P2+.,..) conscious intents from his family and territory tree.

Therefore each individual has a total of E units of energy for all his conscious intents P that could be further split as the following :

Conscious intent P0 has E0 units of energy

Conscious intent P1 has E1 units of energy

Conscious intent P2 has E2 units of energy

.....

Therefore E = E0 + E1 +...

Where each proportion of energy is stored for each of his conscious intents P0 , P1 , ...etc

Let the trajectory of any individual start at the sub-location X0 where there are " k0 " individuals and the individual is expected to spend an amount of dt0 units in the location interaction with the " ko " individuals.

If the individual aligns with one of his conscious intent P1 , then he interacts with k0_1 (out of k0 individuals) individuals for a duration of dt01 units of time (out of the total dt0 units of time in the location).

Let there be " k0 " individuals in the sub-location X0 with their own trajectory that has an information set that includes the locations in their trajectories X_k, the individuals they have interacted in their trajectories k_k , the total conscious intents of each individuals (P_k = P_1+P_2+....) and the conscious intents of all the other individuals they have interacted with (P_k_k) etc

The number of sub-locations which is accessible from the location X0 could be determined by observing all the information in X_k,k_k,P_k and P_k_k . Furthermore the energy distribution for each of these conscious intents stored by each of " ko " individuals along with the energy distribution stored from every of the k_k individuals for their own conscious intents.

The accessibility of any sub-location for the trajectory of the individual is determined by observing the conscious intents from the " k0 " individuals which is stored in " P_k " and observing the conscious intents P_k_k which is stored from various other k_k individuals.

The continuity of all the information is maintained by the individual in sub-location X0 during the interaction of dt0 units with the " k0 " individuals who are then connected to k_k individuals through continuity of information, energy and mass through various other sub-locations.

Every conscious intent from associated interaction of " dt0" unit could be accessible for the individual by observation from his own collection of conscious intents (P = P1 +P1+P3+...) which are interaction keys that are specifically designed to observe relative movement and interact with it which could be used to create or divert location trajectories based on the information acquired from the interaction keys.

Let there be an individual B whose conscious intent P = P0+P1+P2+...+Pn

Suppose if individual " B " has a conscious intent P1 that does not have an energy reserve for the forward trajectory in the location " X0 ". Specifically if the location X0 has a state such that the conscious intent P1 does not align with the observing masculine of the location X0 , therefore individual B cannot interact with the " k0 " individuals in the sub-location X0 to continue the trajectory of the conscious intent P1.

3.1 Introducing deception in the interaction

Since there is no energy available for the conscious intent P1 in the interaction " dt0 " in the location X0, the dt01 units of time cannot be used to interact with one or more of the " k0 " to find sub-locations for the forward trajectory of P1.

Suppose if individual B observes the interaction dt0 units and identifies the sub-location where the forward trajectory of the conscious intent P1 could continue after the current location X0 , he could engineer a deceptive conscious intent to gain access to the sub-location X1 that support the continued trajectory of P1.

Therefore Individual B observes all the conscious intents P_k and P_k_k in the interaction of dt0 units from the " k0 " individuals and all the associated individuals " k_k" and identifies one or more conscious intents (Px) from any and all associated individuals (k0_1) that have the same target trajectory location X1 similar to the forbidden conscious intent P1 of the individual B.

Then individual B fabricates or introduces a false new conscious intent P_false such that it creates a perception through movement that replicates the conscious intent Px and thus allowing the alignment with the associated individuals k0_1. The individual has no energy to create the trajectory to the sub-location X1 from his conscious intent P_false because the conscious intent does not exist , individual B aligns with k0_1 individuals through movement that replicates their conscious intent Px in the interaction dt0 units , such that the trajectories for the location X1 are created and individual B could follow the created trajectory and reach the destination X1.

If the location X1 does not support the conscious intent P1 , the same process is repeated in every sub-location. However this creates an imbalance in energy from the " k0_1 " individuals because , if their true intent was Px then the total energy that was stored from their conscious intents could be described as Ex from each individual. Therefore the total amount of energy that is extracted from the " k_01 " individuals for their trajectory towards the sub location X1 exceeds by a factor of E1 units.

This is because the conscious intent P_false never existed however the forbidden conscious intent P1 existed for individual B , therefore individual B needed energy of E1 units for his trajectory which was diverted from the joint trajectory of the " k_01" individuals.

If the " k_01 " individuals completes their target trajectory from X0 to X1 for their intent Px , they must have diverted a total of (Ex + E1) units of energy from their energy reserves. Where E1 units have energy must have been redirected from the stored potential energy for another conscious intent. Therefore each of the " k_01 " individual would have lesser energy for one or more of their conscious intents that could be left without a forward trajectory as a result of the lower energy.

Individual B completes his trajectory from X0 to X1 for his conscious intent P1 where the energy was harvested through replicative movement deception from the " k_01 " individuals. The amount of energy that was used to create the deceptive movement for the conscious intent " P_false" would be limited to movement energy and would not require creative potential energy. The creative potential is used to plot trajectories for the forward movement where the alignment of movement occurs the change of states in the current location X0 and the target location X1. This change of states does not occur for individual B because there is no alignment for his conscious intent in the current state. Therefore individual B would enter the location X1 under a state that is determined by the " k_01" individuals through their collective potential energy " Ex + E1".

3.2 The application of conscious intent for deception

If the " E1 " units of energy was extracted from each of the " k0_1" individuals by individual B , the energy must have been extracted through the introduction of a conscious intent for each of the " k0_1 " individuals from the engineered P_false conscious intent.

Suppose if individual B discretized the engineered conscious intent as P_false = P_false1 + P_false2 +.... where each of these components was delegated to the " k_01 " individuals under a deceptive narrative, the energy that each component would require would be extracted by their energy reserves.

Where each of the " k_01 " individuals would spend an average of E_1 ,E_2,.... for the respective delegated conscious intents P_false1 , P_false2 ,..... where the total amount of energy spent would add up to the amount of energy required for to establish a forward trajectory of Individual B from X0 to X1 under the deceptive intent.

The application of the delegated deceptive intents P_false1 , P_false2 , ...could be introduced by individual B by merging it with their original conscious intent Px that allowed them to plot a trajectory from X0 to X1. Therefore the amount of time and energy that was required to plot their trajectory would increased by a differential for each individual such as E_1,E_2,...

3.3 The continuity of the deception

Suppose if individual B had no other purpose rather than to consume energy for plotting his trajectories , the effect of his movement through various sub-locations will result in the reduction of creative potential of each sub-location and consequently the overall location X. This is because individual B could travel around the location X through various sub-locations by extracting creative potential energy from various individuals from each sub-locations for plotting his forward trajectories. This creates a circular movement for individual B throughout the location X where each sub-location could serves as a pit stop for a duration of " dt " units to engineer situations such that energy could be harvested for his forward trajectory to the next sub-location.

As a consequence movement drag is also created for each of the " k_01 " individuals that results in their trajectories taking longer than expected in linear time or by increasing the average amount of time spent in each sub-location interaction by an increment deltaT.

Therefore the amount of time spent by each of the " k_01 " individuals would increase from " dt " to " dt + deltaT " , thus delaying the trajectory for their

own conscious intents.

If there are " F " number of individuals in the location " X " completing circular trajectories by introducing false conscious intents P_false1,P_false2,...etc at various sub-locations the amount of energy that is being diverted to redundant trajectories would increase thus stagnating the overall location " X " . Consequently the proportion of true conscious intents P0,P1,P2 ... to the false conscious intents P_false1, P_false2,... would decline thus decreasing the amount of free energy for plotting trajectories in each sub-location.

4 Linear time and the origin of the multiverse

4.1 The Mechanics of hierarchical transition states

Let there be a location " X " created by the prime observer that is defined with a current state at t = T1.

The location would a three dimensional image defined by Dx dimensions of geometrical information such as D1,D2,...Dx

The time T1 represents the moment the prime observer has the (D1,D2,...Dx) dimensions of information in his attention.

Let the prime observer alter one or more of the dimensions of information and create a target state for location " X " at t = T2 which is a variation of the three dimensional geometrical image from state at t = T1

4.2 Creation of Observers

Let there prime observer create three masculine observers O_alpha , O_beta and O_omega with his attention energy to observe the change in the dimensions of the geometrical dimensional information (D1,D2,....Dx) to (D1_new,D2_new,....,Dx_new) that needs to occur from state T1 to T2. The masculine observers could be defined by a set of independent geometrical information (D_alpha,D_beta,D_omega) that interact with dimensional information Dx according to definitions provided by the prime observer.

Where

O_alpha observes all the permutation and combination of changes in the geometrical dimensional information (Dx) that could occur between the states T1 and T2 by creating forward trajectories to all available possibilities.

O_beta observes and interacts with all the permutation and combination of changes simultaneously in the geometrical dimensional information (Dx) that could occur between the states T1 and T2 to determine the optimal trajectory that allows for the continued possibility of creating from transition states indefinitely.

O_omega interacts with all the permutation and combination of changes periodically in the geometrical dimensional information (Dx) that could occur between the states T1 and T2 to removing the non optimal forward trajectories that are ignored by observer O_beta.

The Prime observer creates the location " X " using his attention energy to define the dimensions of geometrical information (D1,D2,...,Dx) and consequently the independent geometrical information (D_alpha,D_beta,D_omega) .

Therefore the functions of O_alpha,O_beta and O_omega are performed by their attention energies which is a branched stream from the attention of the prime observer.

The observers O_alpha and O_beta continually observe and interact with each other between the transition states T1 and T2 by creating " N " transition states such as T1,T_1,T_2,...,T_N,T2. The number of transitions that could occur between the current state and the target state defined by the prime observer could be the definition of linear observation time for the observers which defines their existence based on purpose of creation.

The observers O_alpha and O_beta could continually observe and interact with each other in the " N " transition states thus creating more observers (O_1,O_2,O_3 ,...) hierarchically that repeat the process during the transition states that results in the creation of more observers from various sources that interact with each other.

Where each of the observes O_1,O_2, etc could have their own domains of locations " X " to observe defined by the geometrical dimensional information Dx assigned by the masculine observers who created them based on purpose. The observers could either be (independent or non-independent) defined by their own set of independent geometrical information (D_1,D_2,...)

Since the creation of observers occurs hierarchically the amount of attention energy (creative potential energy) also branches off depending on the amount of energy that each observer would need to observe and interact with various dimensions of geometric information Dx and consequently their own geometrical information (D1,D2,..) .

The amount of creative potential energy to observe and interact with various dimension could be a function of the amount of attention energy that is branched to them from the prime observer based on purpose. Thus higher the hierarchy of the observer , the more the amount of geometrical dimensional information they could control including that of other observers.

Every new generation of observers that are created are assigned dimensions of information Dx that are based on various sub-sets of geometric information (based on purpose and their own independent definition) that are branched from the overall geometric information from the location X.

4.3 The Transition states

Let there was " K " observes (some independent and some not) in the location " X " that are observing various sub-locations and sub-sub locations according to their definitions defined by the masculine observers.

The independent observers may or may not be aligned with the purpose of the prime observer which is maintain the state of the location " X " to continue the possibility of the transition states indefinitely.

Therefore if there are " P " number of observers that are created in the location " X " from the continual interaction between the observer O_alpha and the observer O_beta , there could be " Q " observers that are defining transition states that are counter productive to the transition state of the prime observer. The " Q " observers would also experience a decline in the amount of attention energy to alter the geometrical dimensional information Dx that are being branched to them proportionally from Observe O_omega. As a result , the " Q " observers could functionally only observe and interact with the geometrical information of other observers (D_1,D_2,...) such that they could align their trajectories to create transition states for the " Q " observers .

Therefore the number of transition states " N " is a variable that could change after every transition that occurs . Therefore the shift in the current state to the target state could occur throiugh the multiverse of possiblities that are are created at every transition state.

Suppose if " N1 " transition states are estimated between the current state T1 and target state T2 where the estimation occurs at time T = T1

The first transition occurs at time t = T_1 and the number of transitions from the new current state t = T_1 to the target state t = T2 would be " N2 "

.....

Therefore values of " N " increases or decreases after each transition depending on the number of changes in the geometric information that occur at each transition.

4.4 The correlation to linear time

Suppose if the transition states are observed through linear time , then time between the current state and the target state could change analogous to the number of transitions.

At t = T1 , the number of transition states N1 to the target state could be described as " t1 " units of linear time where " t1 " could be described as time to destination.

At t = T2 , the number of transition states N2 to the target state could be described as " t2 " units of linear time where " t2 " could be described as time to destination.

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Therefore for a linear observer starting at time t = T1 and ending at t = T2 , the time to destination constantly changes from t1,t2,t3,... etc . Where at each transition , the time to destination changes thus altering his timeline reality of linear observation or specifically his location in the multiverse of transition states towards the target state.

In , geometrical form , each transition state that he is currently located in is defined by the exact configuration of the geometric dimensional information defined by (D1,D2,...,Dx) and the geometric dimensions of the observers (D_1,D_2,...) and the relative relocations of the interacting information with respect to the prime observer.

5 Interaction of the observers

Let there be " K " observers in the location " X " .

Let there be a total of " n_sub " sub-locations in the location " X " such as X1,X2,....

Let there be a total of "n_sub_sub" sub-sub locations in the location " X " such as x1,x2,...

Let there be D1,D2,...Dx geometrical dimensional information that describes the location " X "

Let there be D_1,D_2,....D_k geometric information that describes the " K " observers in the location " X "

The prime observer of the location " X " defines the prime transition state from T1 to T2.

Let " P " observers be aligned with prime observer

Let " Q " observers be mis-aligned with the prime observer.

Let the current superposed transition state of location " X " be defined as " Y " where each of the observers have defined a transition state from current at T1 to target state at T2.

5.1 Movement drag between transition states

The time of observation T1 and T2 is defined independently by the observers by observing various dimensions of information Dx and the geometry of other observers (D_1,D_2 ,..) who are interacting with the geometry Dx.

The transition states are set in movement by the observers by creating an interacting observer at various sub-locations or sub-locations who then observe and interact with the geometry through observation of linear time.

If there are two contradictory states for the location " X " by various observers , then the resolution of the contradiction occurs through the interaction between the interacting observers from the masculines who have defined their own states. Since the contradiction could only occur when contradictory dimensions of information intersect at various sub-location or sub-sub locations where both the interacting observers are creating movement for transition.

Suppose the current state of location " X " is defined by " Y " , one masculine observer alters the target state to " Y_new " and starts the transitions at various sub-locations and sub-sub locations.

5.1.1 Movement drag metrics

The interacting observers interaction interact for a duration of " dt " units in linear time where the transition state of one of the interacting observers is altered . The factors that determine the interaction of the state resolution depends on the following metrics :

1. The prime observers 's alignment with state which may or not include his observation for his prime transition state.

2. The creation hierarchy of the observers interacting where one of the higher order observers could observe more information about the other thus allowing more trajectories to interrupt the transition state of the other observer.

3. The amount of kinetic energy in the transition state that is ongoing from each observer

4. The amount of potential energy that is stored by the observer to intercept the other transition state

5.1.2 Observer conflict Illustration

Suppose if there are there are two observers A and B that are interacting then the interacting observers A and B will interact in a sub -sub-location " x1 " for a duration of " dt " units of time where one of the individuals will alter the trajectory of the other.

Let observer A be the masculine which implies that observer A could observer the trajectory set by observer B and the interacting individual B in more detail than observer B being able to observe the trajectory of observer A .

During the interaction the kinetic energy from the ongoing transition states from Observer A and B will interact with the timeline flow of their respective trajectories creating movement drag for both individuals in their trajectories. When the kinetic energy is fully lost in the drag , the observers could use their stored potential energy to create further movement drag until the energy reserves run out.

When the energy reserves of one of the individuals run out , the trajectory with the energy will continue while the trajectory that has no energy will stay frozen.

Let " dC " be the amount of time that is required to recharge the reserves of the individual who had lost the energy at which point the individual will intercept the trajectory of the other individual for another duration of " dt1 " units until the energy runs out.

The process will continue until one of the conditions is satisfied :

1. One of the individuals will successful end the trajectory of the other.

2. The interaction of the transition states will continue until one of the individual will permanently run out of energy

3. The trajectory of one the individual will change from sub-sub-location " x1 " to sub-sub locations " x2 " where the other can no longer access the location " x2 " which is not defined through his transition state.

The interruption time could therefore be defined as the following :

dt units of time at location " x1 " - The movement drag for the trajectories continues until one of the individuals runs of out energy

dc units of time - The amount of time that is needed to recharge the creation of potential energy of the individual

dt1 units of time at location " x1 " - The movement drag continues for both the individuals

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5.1.3 Resolution of the transition states

The process continues until one of the individuals completes his transition state at sub-sub location at " x1 " and changes his location to sub-sub location " x2 " to continue his transition state movement defined by his respective observer.

The individual who fails to complete his trajectory at " x1 " that defines his transition state movement can longer interfere with the state set by the individual who completed his transition trajectory at the sub-location " x1 ".

The failed individual cannot enter and intercept the individual at location " x2 " unless there is a state entanglement between the locations that allows his

trajectory to enter the location " x1 " . If there is no entanglement or the entanglement is broken by the individual changing the state from " Y " to " Y_new " , the failed individual cannot enter the sub-location " x2 " because it is no longer part of his trajectory that defines his linear observation of transition state defined by his masculine.

6 The interaction of the prime observer

Suppose if an observer A was created for the observation of location " X " , he could observe the geometrical dimensions of the location X such as D1,D2,...Dx that describe the location X.

The conscious awareness of Observer A does not exceed beyond the location " X " , therefore observer A does not have access to any dimensions of information other than D1,D2,...,Dx .

Suppose at a current state t = T1 , the observer defines a new target state t = T2 by altering the dimensions D1,D2,...,Dx.

6.1 Creating new locations from " X "

The creation of new locations based from current available information D1,...,Dx such that a trajectory could be plotted to the new location from the current location X requires the ability to :

Observe all current sub-locations X1,X2, etc within the location " X " and consequently the dimensions that describe each sub-locations (D1,D2,...,Dx1), (D1,D2,...,Dx1)...etc

The process of observation requires attention energy that depends on the hierarchy of creation for the observer that defines his spectrum of observation. If he could observe every dimension from every sub-location could be assumed to be exponentially growing, then he would need the spectrum of attention energy that continually expands all the scales and dimensions of information that are being created.

6.2 Creation of locations and continuity

The amount of energy that goes into the creation of the new location is defined by the amount of attention energy that could be diverted from an observer from the location " X " .

If there is a hierarchy of observers starting from the prime observer and attention energy is funneled through the higher order observers to the lower order observers based on their purpose, then each observer could have an attention spectrum that is explicitly defined by his masculine observer.

The attention spectrum would define the boundary conditions of his percep-

tion for his consciousness, and it could have a definition based on the geometric definitions of his territory of interaction and the other observers who are interacting in the territory.

The larger the spectrum of the attention energy, the larger the scale and dimension of the observation thus larger the larger the amount of geometric information along with the geometry of observer he could observe thus having more information to regress new locations.

The locations that are created by a lower order observer and a higher order observer would differ by the number of dimensions of information that defines the locations. This is because the higher order observers would have a larger attention spectrum and thus define it more detail while the details used by lower order observers could be limited to their spectrum.

The attention spectrum from the lower order observers is branched from the higher order observers and therefore the attention energy that flows through the spectrum would therefore have a hierarchy of control on where the energy flows.

Therefore any location that is created or regressed by the lower order observers could be invalidated or erased if the attention energy from the higher order observers is re-diverted from those locations to other locations.

If the higher order observers do not directly observe the locations or the observers originating from the locations that have been created by the lower order observers, the existence of the locations or the observers do not stabilize or could even destabilize depending on the intent of the higher order observers.

6.3 The Prime observer

The definition of prime observers could be the ability to create a new location with no amount of pre-defined information.

If there are " K " independent life forms that have developed in " K " independent locations completely isolated from each other, then it must have been created by " K " independent prime observers or one prime observer with " K " different variations of geometric dimensional information from his attention spectrum.

Consequently, the prime observers could also define the current state and the target state at various transition states based on various criteria of change for the geometric dimensional information.

The prime observer could then create interacting observers in the location " X " after defining the target state. The interacting observers observe the location " X " in linear time to ensure the transition towards the target state.

The observation of the current state could occur by a linear observation of the current state through various sub locations at the current state including the geometric information about the other interacting observers in those sub-locations.

The interacting observer could then define the transition state by reassigning the relative locations of other interacting observers in the location X to create a new transition state that will redefine the geometric dimensional information according to the newly defined target state. The redefinition could include reduction, branching or exponentially increasing the geometric dimensional information.

The newly defined transition state will redirect the overall kinetic energy from the location X from its current state towards transition states that define the target state for the location X.

In the sense of linear observation, the flow of time represents the movement of transient states where each intent of movement is segmented by a duration of time. by various interacting observers.

The newly defined transient states could also redirect the stored potential energy towards the creation of the new transient states which is essentially the creation of new movement by the interacting observers which is defined by an intent that is defined by a duration of time.

6.4 Creation of observers

Suppose a masculine observer O_2 directs his flow of attention energy to various dimensions of geometric information D_new in the location " X " to observe and interact with it as a whole, it would create a collective consciousness O_new to observe and interact with those dimensions of information as a whole.

The masculine observer could then observe and interact with O_new that could interact with the location " X " through the " D_new " dimensions and consequently the other observers who are interacting with those dimensions in the location " X ".

Exchange of information could occur between the observers O_2 and O_new which could include transition state information of the location " X " , the relative locations of interacting observers , the intent of the interacting observers in the surroundings etc.

The duration of existence for the observer O_new could be defined by the duration if its purpose or until the attention energy that is fueling its existence no longer exists.

If the defined dimensions of information for the observation and interaction for the observer O_new is based on purpose , it could even allow O_new to control the movement of other interacting observers and geometry based on the dimensions D_new .

The consciousness of the observer O_new could be a copy of the observer O_2 with a different set of interaction keys in the surroundings that share a common purpose aligned with observer who created O_2 and so on. Thus the shared purpose of creation is linked hierarchically .

Since the prime observer is the first observer of the location " X " , any observers O_1,O_2 etc could detach from the purpose of the prime observers thus becoming independent mis-aligned observers . Thus the observer O_new is either is aligned with the prime observer or mis-aligned.

6.5 Creation of Masculine primes

Suppose if the creating consciousness could create an entity that could observe and interact with all the dimensions of information that are currently in existence in the location " X " , then the entity could have control over all the dimensions of geometrical information including the geometric information of the observers. Therefore, if the dimensions of information are continually growing then the conscious awareness of this entity could continually grow.

The consciousness of such an individual would be the copy of the consciousness that created it.

Suppose if the first conscious entity was the prime observer, he could create such three prime observers (O_alpha, O_beta ,O_omega) to define the transition towards the target state of the location " X " . They would be three copies of the prime observer with varying interaction keys to observe and interact with the location " X " based on their scale and dimensions of their perception.

Where :

O_alpha would observe and interacted with all dimensions of information defined by a purpose to create all possible forward trajectories for the transition state of the location " X ". This could be achieved by creating a sequence of observers O_1, O_2,....etc. to observe and interact with various dimensions of

information D_1,D_2,.... etc

O_alpha would observe and interact with all the probable observers created by O_alpha to determine the optional transition states for the target state set by the prime observer.

O_omega would observe and interact with non-optimal transition states created by O_alpha and the associated observers either by erasing their existence or redefining their interaction keys.

6.6 The sequence of Masculine primes

The creation of various masculine primes (O_prime1, O_prime2,.) by the prime observer or various primordial iterations of the prime observers (such as O_alpha,O_beta ,O_gamma) that have a higher order control of various dimensions of geometric and observer geometric information that could alter the mechanics of the movement of relative geometry (of location " X ") and observers of the geometry.

Therefore, the amount of attention energy that is channeled to the masculine primes from the creating consciousness (prime observer) would be maximum. Therefore, they could hold a larger control over the location " X " and they could be commonly called as deities or demi-gods or archangels in various subcultures.

7 The Aligned and the mis-aligned observers

Let there be a prime observer who creates the location " X " at current time t = T1

Let there location " X " be defined by a geometric structure with a fixed set of dimensions defined by a set of vertices that define its outmost points (Dx). The location " X " has a volume " V " at the time of observation at t = T1

Let the prime observer create another state for t = T2 (defined as the target state) for the location " X " by redefining its geometric information (Dx_new) and ultimately changing its volume to " V_new "

Let the prime observer create three observers " O_alpha ", " O_beta " and " O_omega " to observe the transition from the current state to the target state . The prime masculine observers could be created in every possible location inside the location " X " and outside the location " X " . The location of the masculine observers outside the location " X " be the location of the prime observer. However the interaction keys of the prime observers could be defined such that they could observer and interact with all the dimensions of in formation in existence which would be Dx, Dx_new and every possible variation of the geometric information in the N transitions (Dx_1,Dx_2,Dx_3,..) that could occur between the current state and the target state. The attention spectrum of the prime observers could be expanding to observe the increasing number of dimensions of information.

The location of the observers could be defined as follows :

The locations of the observers are defined based on the dimensions of geometric information that are changing from the current state to the target state defined by Dx. Let the location " X " be divided into " N " locations and

" n " sub-sub location in the location " X ". Depending on the which segment of the location the change in the geometric changes need to occur , the observers are placed relative to each other.

Suppose if the transition state requires prime observers in " K_sub " location and " K_sub-sub " locations to be altered by redefining the geometric information in these locations then , there are a total of " K_sub + K_sub-sub " observers to observe the transition state from T1 to T2. Since the " K_sub-locations " and " K_sub_sub locations " may have intersecting areas defined by the overall change by the geometric dimensional information " Dx " to " Dx_new" , a collaborative observation will need to made implying that the transitions that could occur independently in each sub-sub location and sub-location will need to be aligned with each other along with the overall transition at the location " X"

Suppose if the total number of locations where an observer could be required is defined by " K = K_sub + K_sub-sub " , then the prime observer could create " K " prime interacting observers where attention energy from the masculine observers could be diverted when the observers are aligned with the prime observer. The masculine observers could divert their attention to the various " K " locations depending on their interaction keys and functionality that would align with the intent of the observers in those locations.

7.1 The iterative process of interaction in the transition

The transition process from the state T1 to T2 occurs with the hierarchical creation of observers through out the location " X " . Therefore the process of creating interacting observers at various locations would be the interacting process during there transitions.

The transition process then takes the form :

1. The prime observer creates a target state for the transition in the location " X "

2. The prime observer creates masculine observers O_alpha , O_beta and O_omega in every possible location of the location " X " for the transition process

3. The masculines observers then identifies the " K_prime " locations where the transitions need to be observed and creates " K_prime " interacting observers.

4. The observation and the interaction of the " K_prime " observers become deterministic because the the attention energy is diverted directly from the masculine observers from the prime observer.

5. The " K_prime " locations could determined based on the law of minimum action to minimize the interaction with other other observers and their ongoing transition states.

7.1.1 The Aligned Observers

Suppose if the number of transition states from the current state of observation t = T1 to the target state of observation t = T2 changes at each transition state then,

Suppose at time t = T1,

The number of transitions to the target state t = T2 , the number of transitions are defined by N1 . The number of transitions are estimated by the prime masculines (O_alpha, O_beta , O_omega) by collectively observing the location " X " from every possible location inside and outside " X " . The prime masculines then determine the " K_prime " locations for the observation and then alter the locations of the prime observers " K_prime " towards those locations for interaction. For the interacting prime observers , their prime timeline is defined by the time t = T_1 units of linear time towards the target state set by the prime observer.

Suppose at time t = T2 ,

The same process is repeated , the number of transitions is determined to be N2 . The prime timeline changes to the one defined by t = T_2 units of linear time towards the target state set by the prime observer.

....

Therefore at each transition state , the prime masculines alter the prime sublocations " K_prime " where the transitions need to occur based on the optimal transition trajectory from the new current state to the target state. Consequently the optimal timeline for the prime observers is defined by the T_1,T_2,T_3 units of linear observation of continuous time.

Therefore after each transition in the multiverse , the prime observers remain in the prime timeline where the time to destination changes thus changing their timeline reality that is defined by their locations which defines the optimality for target state set by the prime observer.

7.2 The Stochastic transitions

Suppose if there were only aligned prime observers in the location " X " , then the transitions could occur without any conflicting transitions states and the number of transitions N1,N2,... would be in a descending order and consequently the time to destination T1,T2,... would also be in descender order. However there could be two kinds of observers in the location " X " , observers who are aligned with the prime observer and observers who are mis-aligned with the prime observer. If all the aligned observers are created by the prime observer or the prime masculines then the origin the creation of non aligned observers could in the transition states.

7.2.1 Creation of other observers

Suppose the prime observers , and the masculine observers could create other various other observers (O_1,O_2,...) hierarchically for various transitions in the location " X " , then it could be branched off into observers of the following categories .

1. Non interacting observers in various locations (Interacting observers created for no particular purpose)

2. Interacting observers whose transition states have been interrupted or redirected.

3. Interacting observers who have voluntarily mis-aligned their purpose with the prime observers to create conflicting transition states

Let there be " P " observers in the location " X " that are aligned with the prime observer and " Q " observers in the location " X " that are mis-aligned with the prime-observer.

7.3 The Mis-aligned observers

The " Q " observers could either independently or collectively define their own transition states for various sub-locations that may be contradictory to the transition states that are established by the prime observers . The contradiction creates the variation in the number of states " N " after each change of state along with the time to the target state " T " in linear time for the prime observers.

Since the " Q " observers are mis-aligned with the prime observer , the amount of energy that is available to them would be severely restricted or not available . Therefore the " Q " observers could collectively create transition states where various sub-locations or sub-sub locations " K_harvest " could be defined exclusively for harvesting energy from various prime masculine aligned observers in the location " X " .

Therefore " Q " mis-aligned observers could create the following kinds of contradictory transition states that variable " N " and " T "for the prime observers.

1. Transition states to harvest energy from the location " X ".

2. Transition state to maintain the overall target state of location " X " set by the masculines of the mis-aligned observers.

3. Transition states to alter the perception of the prime masculine aligned observers

4. Transition states to alter transition trajectories of the prime aligned observers (that often conflicts with the mis-aligned masculines)

Since there are more contradictory transition states than aligned transition states could be occurring in the location " X " , the variables " N " and " T " show random variation at point of observation by the prime observer . The variation of the number of transitions and linear time will result in the creation of more geometric dimensional information (D_new) of the location X along with the new geometric information of various observers (O_new)

If the prime observer chooses to interact with the law of minimum action then , the variables " N " and " T " could either grow in ascending order or remain constant , on the other hand if the prime observer chooses to violate the law of minimum action either out of boredom, mis-aligned target states (that could be irreversible due to entropy) , he could make the variables " N " and " T " deterministic at each transition thus creating a convergence streak towards the target state for the location " X " at t = T2.

8 Time reversibility of geometric observers

Let there be " K " observers in the location " X " . The location " X " has been sub-divided into " n " sub- locations.

The location " X " is comprised of information where Dx represents the geometric information of the location " X " and Ox represents the observer information (location of the observer and interaction metrics with their territories) interacting with the location " X " through the information Dx.

The " K " observers could perceive the location in discrete time such as t = T1,T2,...etc. where the location " X " could be perceived as a three dimensional image .

The " K " observers observe the current location " X " at a time t = T1 and define the current state with the geometric dimensional information Dx and the observer information Ox .

The " K " observers then redefine the geometric dimensional information as "Dx_new" and the observer information "Ox_new " and define a new state t = T2 called the target state.
The " K " observers then create " N " transition states between the current state t = T1 and the target state t = T2 defined by the T_1,T_2,...T_n

8.1 Defining the transition states through the three dimensional image

Let the geometric definition of the location " X " such as length , breadth ,height, volume " V " is defined by the geometric information Dx at time t = T1 of observation.

Let the observer information Ox define the locations of the observers in the location " X " along with the attention vectors of the observers. The attention vectors of the observers define the energy flow from the observers to the surroundings such as the location of other observers, various geometric components such as sub-locations , sub-sub locations etc.

Therefore the attention vector of the observers could always be directed to a specific territory defined with length, breadth ,height and volume " V_1 " . Therefore depending on the attention spectrum of the observer , his attention vector could leave an energetic trail to " Z " such territories in the three dimensional image.

Suppose if there are " K " interacting observers in the location " X " , there

could be " K * Z " attention energetic trails from the observers to various territories in the location " X " that may be unique or repeated.

Suppose at the next transition state t = T_1 , if the observer does not interact with the attention vectors of the interacting observers then there could be " K * Z " possible three dimensional images possible depending on the choice of each observer for his next trajectory. Therefore if the free will instinct of the observers are choosing the next trajectory then choice made out of " Z " trajectories from each will be reflected according to the transition for the target state set by the prime observer.

8.2 Interaction of the observers with attention vectors

Let one or more of the " K " observers define a transition state at t = T_1 such that , the observers from the target state t = T1 are relocated and the attention vectors of each observer leaves an energetic trail to specific territories in the location " X ". Therefore the three-dimensional image defined as the transition state at t = T_1 using the reference three dimensional image from the state at t = T1 is engineering the attention vector of the observers in the location through the following process :

1. Identify the number of interacting observers O1,O2,...,Ok in the location " X "

2. Identify the number of free will attention vectors from each observer thus identifying the next probable trajectory Z1,....,Zk

3. Apply an external force in the location " X " such that the choice of the next trajectory for each observer O1,O2,... could be reduced to the chosen target trajectory set by the observers such as :

Z1 possibilities will converge to Z_t1

Z2 possibilities will converge to Z_t2

....

Where Z_t1 , Z_t2 are the target trajectories for each observer such that the target transition state defined by the " K " observers could be achieved.

8.3 Altering the attention vector of the interacting observers through perception

Suppose if the masculine observer for the " K " observers is aligned with one or more of the interacting observers through the process intent transfer by repetition. This process could be be achieved by the masculine observer by observing the attention vector of various interacting observers at various transition states such as T_1,T_2,... and the masculine observer sorts the interacting observers based on the locations that are there in their attention vectors.

If there are " n " sub-locations , then each of the " K " individuals could be sorted as the following based on probability . Suppose if the masculine observer could observe " N " transition states or three dimensional images , then each of the K individuals could be observed for the frequency of their attention vectors that is energetically aligned to various locations and sorted .

Individual one had his attention vector on sub-location X1 on all the N transition states

Individual two had his attention vector on sub-location X1 on most of the N transition states , X2 on other states

Individual three had his attention vector on sub-location X2,X5 and X6 in equal proportions

.....

Suppose the observing masculine would like to engineer a situation where he would his priority would be X1,X2 and X3.

Then the K (interacting observers) individuals (K = K1 + K2 +...) in the location " X " could be sorted as follows :

1. K1 individuals have their attention vector on location X1 with a highest probability.

2. K2 individuals have their attention vector on location X2 with highest probability

.....

Therefore the locations of various interacting observers could be re-arranged in the location " X " such that the three dimensional image that is expected in the transition state t = T_1 starting from state t = T1. Therefore the movement that occurs such that the locations of the " K " interacting individuals in the location are rearranged defines the intent of transition. The movement requires

energy to initiate that creates a continuous flow of time such the relative change in geometry occurs. The continuous flow of time is initiated from the timeline of the masculine interacting observer in the location " X ".

8.4 Initial Alignment of the masculine observer with the interacting observer

Suppose if the masculine observer could isolate one interacting observer at a sub-location " X1 " and observer his movement through the natural movement of his attention vector then at some point his trajectory will change to sub-location " X2 ". For the interacting observer , the flow of time would be continuous in the sub-location and his observation would be the linear rate of change of geometry.

The observing masculine observes the movement trajectory of the interacting observer through three dimensional images at specific points of observation. Suppose the observing masculine creates " N " transition states for the interacting observer in the sub-location before his location to the sub-location X2 , then the observing masculine could observer the " N " three dimensional images and specifically his attention vector and identify the next trajectory that is expected in the next transition state or image.

If the observing masculine could interact with the interacting observer at any of the transition state t = T_1,T_2 etc , he could communicate to alter his attention vector from one location to the other . This process could only occur if the interacting observer has his attention on the observing masculine in one way shape or form. Therefore this creates or establishes an energetic continuity from the observing masculine to the various sub-locations in the location " X " through the interacting individual who acts as an interface for the communication. This would then allow the observing masculine to redirect the movement trajectory of the interacting observer to various other locations.

Suppose if enough communication occurs between the observing masculine and the interacting observer where the attention of the interacting observer is consistently on the masculine observer , the movement pattern of the interacting observer and the observing masculine could be identical thus merging their movement vector field through their instincts. Therefore this creates a copy of the observing masculine in the sub-location " X1 ". If the process continues from one sub-location to the next , then the trajectory of the interacting observer could be copy of the transition intent of the observing masculine towards the target state.

For the interacting observer who observes the trajectory in linear time in the sub-location " X1 " , his behavior trajectory would be identical to the observing masculine where one of his driving forces of movement would the observing

masculine that could be reflected in the amount of time that the interacting observer has his attention on the observing masculine.

8.5 Identifying the current moment of the interacting observer

Suppose if an observing masculine has observed the natural flow of the attention vector from an interacting observer at the sub-location " X1 ". The movement trajectory of the interacting observer in the sub-location " X1 " could be isolated by the masculine observer. While the interacting observer observes hos trajectory through linear time , his entire presence in the sub-location " X1 " is defined by a duration " dt0 " units.

The interacting observer enters the sub-location " X1 " at time t = 0 and exists the location at time t = dt units. The attention vector of the interacting observer flows time like a fluid from start to finish where there is an energetic trail from his exact location (sub-sub location) in X1 to the surrounding " sub-sub locations ".

For the observing masculine to interact with the interacting masculine , he needs to identity the exact sub-sub location where the attention vector of the individual exists at the time of interaction. Identifying the exact sub-sub location where the attention vector exists identifies the current moment where the energetic link exists. Identifying this active energetic link would allow the observing masculine to intercept and alter his trajectory ,. in some sense it could be taking command over the trajectory of the individual where his real time attention trail could be diverted or distracted as and when necessary.

For this process , the masculine observers needs alignment with one or more interacting observers simultaneously because engineering the intersection of these interacting observer in a sub-location or sub-sub location through a defined interaction of duration of " dt " units. Once the current moment where the three interacting observers could be engineered at a sub-sub location , this creates alignment in the time flow between the interacting individuals, or in other words aligns their timelines together. The synchronization of the current moment will create parallel time flows where the intersecting interactions describes a merger of information that occurs for their forward trajectory which enables their time flows to remain synchronized. For the masculine observers of these interacting individuals , it allows them to track the current moment of energy transfer between their timelines relative to each other.

Therefore such aligned interactions from various interacting individuals , will enable the masculine observers to track the location of attention energy sources in real time from various interacting observers and consequently the energy re-

serves from masculine observers that are aligned with the prime observers.

The information exchange that occurs in these intersecting interactions could include information about the past trajectories such as the locations that he visited , the amount of time that he spent in those locations , his current location and the expected amount of time that would spend in the location and his probable locations in his forward trajectory.

Once the interaction that aligns the current moment of various interacting observers could be identified , then it could be used as a boundary condition to start new transition states that are defined by the location and time information to control the trajectory of the interacting observers.

8.5.1 Identifying the current moment or the present in the time spectrum

For this process to work , the masculine observer must be fully aligned with atleast one interacting observer which essentially implies there must be complete alignment in the movement instincts which could only occur if the observing masculine is entangled completely with one of the interacting observers. The implication would be that the masculine observers the movement of interacting observer along his linear observation of time which gives him a reference point for the current moment of the interacting observer.

This alignment is used by the masculine observer to create intersecting intersections that will allow him to identify the current moment of various other interacting observers and align the present from all the intersecting timelines. This enables a live stream of attention energy to be harvested by the observing masculine for expanding their timelines by creating transition states towards various target states that may or may not include expanding the location "X".

8.6 Engineering the trajectories by the masculine observers

The overall collective perceptive of the current moment (present) aligned interaction has a descriptive flow of information where their stored potential energy of the interacting observers could be directed to for the next one or more transitions. This is regressed by the masculine observers by observing the real tine flow of attention energy from each interacting observer to various sub-locations or sub-sub locations.

Forcing the change in the rate of attention energy flow from one or more interacting observers towards various locations will affect their future trajectories or

transition states.

8.6.1 Predicting and engineering the diversion of the attention vector

The descriptive perceptions of various locations where each interacting observer spends a duration of time with " k " individuals could be defined as an intent which could also define the relative locations of various individuals in their future interactions in their trajectories. The relative locations of all the individuals in the interaction is correlated to the attention vector of each individual that defines their real time directional flow of attention energy. The change in the relative locations of various individuals will either divert or redirect the attention vector of various " k " individuals in the interaction. The interaction will define the overall perception at the present moment of time specifically the transition state that is occurring and therefore altering the relative locations of the " k " individuals will divert the trajectory of the individuals to a different transition state.

8.7 Engineering the attention vector to create perception

Creating intent at any given location through an interacting observer over a period of time could occur by establishing a pattern of specific information and associating a sub-location for the attention vector when the specific information is recognized. This could automatically redirect the attention vector of various individuals when the pattern of information is observed in any interactions. The redirection occurs by altering the perception of the individual with an external force created from the kinetic energy of the time flow.

An intent is therefore defined in the interaction for a duration of dt units where the attention of the individual is highlighted to a sequence of information such that when the individual observes that specific sequence of information, the attention vector of the individual shifts towards the programmed implication or the intent. The intent could be programmed into the consciousness of various individuals through an interaction with a sequence format such as:

Let there be an interaction duration = dt units

Casual information exchange (replace and repeatable) occurs = dt0 units

Narrative one with highlighted set of information for a duration of = dt1 units

Casual information exchange (replace and repeatable) occurs = dt2 units

Narrative one with highlighted set of information for a duration of = dt3 units

....

Therefore, the interaction duration dt could be split as = dt0 + dt1 + dt2 + dt3 ...

The highlighted sequence of Programmed intent information narratives has a total duration = dt1 + dt 3 +....

The purpose of the programmed intents to divert the attention vector (change perception) of the individual where there is a set of combined set of information from narrative one, two ,.. in an interaction in the future trajectory. The change in perception will alter his location trajectory to the one programmed in the engineered intent.

This process could be used to alter the current trajectory of any individual by shifting the association between various narrative sets in their perception by replacing their attention vector response from default to a programmed one

8.8 Time independence of programming intents

Suppose if the present of the interacting observers could be identified specifically their ongoing energy trail from their attention energy in real time , this would allow access to the stored creative potential energy from these individuals that could be used to alter the location " X " through various means. While the attention energy could be sufficient to create transition states by the observing masculines in three dimensional image form , the creative potentiate energy would be required to initiate transition movement from static transition state to another through the creation of the time flow set in motion by the interacting observer.

Since unaligned observers do not access to reserves of creative potential energy , this method of energy harvesting would provide the source of energy to extend their timelines.

If the present of the interacting observers could be intercepted through an interaction location , the real time attention flow could be used to alter their attention response to the narrative (perception) of the interaction. This could be established from the location and time information that is available in the interaction of various interacting observers along their trajectory.

If one of the location could be identified where the individual had spent a du-

ration of time " dt " units in the location , then if there is a possibility of intercepting one or more interacting observers in that interaction of " dt " units through the current interaction (present) , the energetic connection through the real time attention energy flow could be used to create a transition state where the creative potential energy could flow from the current reserves of the interacting observers to create an alternate trajectory where the individual's attention response could vary from the present interaction. The masculine could then force the present interaction to the altered trajectory by engineering the attention vectors of all the individuals in the current interaction to mimic the hypothetical trajectory.

If enough attention energy and creative potential energy is diverted to reflect the perception of the hypothetical quantum state of the trajectory , the interaction could serve as a portal to the altered trajectory.

The process could then be analogous to creating a quantum channel to access a version of individuals from a parallel timeline where the perception of an interaction in the past would be different that what what was assumed at the start of the present interaction.

The masculine could then replace the perception of the interacting observers either through persistent hypnosis or other mind altering techniques specifically altering the narrative of the past interaction through a more receptive state of consciousness which may or may not include mind altering drugs or technology.

Therefore using a quantum state of possibility , the same process of programming intents could be achieved under the right circumstances.

9 Perception of movement

9.1 Defining the timeline as a the transient time flow between the transition states

Let there be a location " X " where there are " K " masculine observers.

Each masculine observer independently observes the location " X " as a three dimensional image at a current state t = T1 and defines a target state t = T2.

The masculine observers create interacting observers in various sub-locations to create the transition from the current state to their defined target state. The movement of independent observers in the location X could occur relative to the locations of other observers in the locations.

The interaction of the interacting observers creates flow of attention energy that form a webbed network of information exchange that occurs in an iterative sequential order through various sub-locations and sub-sub locations in the location " X " .

The timeline or the time flow is created with respect to the geometrical dimensions of the location " X " by each masculine observer to initiate the transition state towards his defined target state.The process would require an amount of creative potential energy to alter the various boundaries of the location " X "

The potential energy is converted into kinetic energy through the time flow that applies an external force to the attention vectors of all the observers in the specific territory of the time flow.

9.2 Defining Perception

The perception of relative movement that is occurring in the sub-location is defined by the webbed network of attention energy that is being observed and interacted with by each individual.

The perception of the individual is defined by the boundary conditions that exist in each interacting individual that is defined by the number of " P " conscious intents that is part of his perception. Each conscious intent has a scale and dimension of observation that defines the overall geometric structure that must be isolated in the surroundings by using his attention energy and the relative movement of the individual with the isolated geometric structure will define the transition state in the location.

If this process occurs naturally then the attention energy is diverted according

to the time flow or timeline created by the masculine , however if this process is interrupted by one or more time flows or timelines from various other masculines in the territory , then the natural flow of attention energy to the webbed network of geometric structures defined by his perception is altered.

Suppose the movement of every interacting observer could have three narratives for the movement in the territory that is occurring such as :

1. The objective narrative where his movement is defining the transient state defined by an observer either aligned or mis-aligned with the prime observer for the target state set for the location " X "

2. The true illusion where the interacting observer is observing the rate of change of geometry in the surroundings (relative to his own location) with a narrative that he presents to the various groups of interacting observers in the surroundings such as friends, family etc. that describe his intent for movement.

3. The deceptive illusion where the interacting observer is observing the rate of geometry in the surroundings (relative to his own location) with a narrative that is relative to his true illusion. This could occur if the narrative of the true illusion that he could present to the surroundings would create movement drag to his trajectory.

Therefore the purpose of his movement relative to the surroundings could have a hierarchy of reasoning defined by Geometric narrative, True Illusions and Deceptive illusions.

9.3 Geometric narrative

The objective geometric narrative of the interacting observer that is defined by the masculine observer who created the interacting observer to create and alignment in the surroundings according to the transition state defined. This could be defined as the continuous flow of geometric information from one observer to another to align the overall changes in the external geometric boundaries according to their territories that is aligned the overall geometric configuration of location " X ".

9.4 True Illusions

The true illusions are created by the perception of the individuals that creates an umbrella narrative over the geometric narrative that may or may not be correlated to the geometric narrative. This is created because of the delay

that could be caused between the exchange of geometric information which is dynamic and iterative in nature. Suppose if an observer is location in any territory for a duration of T units of linear time , then " T " units of time must be the amount of time that lies outside of his perception (unobserved time) exchange of geometric information is occurring to complete one or more cycles of information exchange in the territory until the transition state is completed in that territory. Therefore this " T " units of linear time for the interacting observer could include " N " number of transitions states that are created, aligned or diverted from various individuals to align their current moment or present where their attention energy could be co-ordinated to harvest their creative potential energy that is required to initiate transition states in various territories in the location " X ".

Since these transitions occur outside the perception of the interacting observer , the " T " units of linear time could be used for an umbrella narrative in the territory in alignment with the " k " interacting observers in the territory. The umbrella narrative could take any form such as family, friends, colleagues depending on the relative locations of the interacting observer to each of these " k " individuals.

The true illusions are a natural consequence of the linear observation of continuous time for a period of T units in any location. Therefore the lifetime of the interacting observer or the individual is a sequence of linear observation of continuous time in various locations such as :

T0 units of time in the location X0 where the interacting observer is created or born

T1 units of time in location X1

T2 units of time in location X2

.....

Tn units of time in location Xn where the interacting observer completes his transition cycle or dies.

9.4.1 The Point Universe

The alignment in the narrative between the true illusions and the objective geometric narrative could vary significantly from having no alignment to having full alignment. On the other hand the conscious awareness of each narrative about each other could also vary from having no awareness to having full awareness. The true illusions and the objective geometric narrative are assumed to be ob-

serving and interacting with independent boundary conditions and consequently their frequency of existence could also vary .

Where the objective geometric narrative could be assumed from the point consciousness of any interacting observer that is from a universe or a time that is purely geometric in structure and any movement that is occurring in any location is simply a rythmn of geometric shapes and structures are iterating to create more complex geometric structures . The movement could be represented an iterative approach where segments of the geometric structures are being observed independently , selectively or as a whole to achieve optimality in the structure that allows for the continued growth of that structure.

The timeline or the universe where perception is limited to the relative movement of point consciousness is called as the " the point universe " and it is the home of the prime observer.

9.5 Deceptive illusions

The deceptive illusions are created by the perceptions of the individuals relative to the objective geometric narrative and / or the true illusions of the individuals. The purpose of creating the deceptive illusions could depend on the narrative from the true illusions or the objective geometric narrative.

The deceptive illusions could be created for the purpose of T units of linear time observation which could be independent of the geometric objective narrative. Under this context , the deceptive illusions could be used to control relative movement based on the interests (likes/dislikes) of the individuals which is correlated to the experience of the " T " units of time in various locations. The deceptive illusions could also be used in various locations to extract creative potential energy by forcing the attention energy of " k " individuals to align with the current moment (present) of the interacting observer thus establishing an stable quantum channel through which energy flow occurs.

The deception illusions could also be used as the umbrella perception to gain access to various locations for the geometric objective narrative . If the interacting observer has conscious awareness of the geometric narrative and the relative movement drag that he could experience in his trajectory , then it would be a form of deceptive illusion , however if the interacting observer has no conscious awareness of the geometric narrative or the movement drag that it could present to the trajectory of the individual, then it would remain a true illusions. Under the context , the difference between the true and deceptive illusion of the perception would the amount of energy that could be accessed from the point universe which could be voluntary or involuntarily in accordance with the prime observer.

10 The Geometric Consciousness

10.1 The geometric manipulation of movement nodes

Suppose if the consciousness geometric coordinate system of any individual could be deactivated temporarily dor a duration of time T units .

The life-force movement of any individual could be directly correlated to the consciousness that is navigating the movement nodes such as legs, arms and other biological organs .

but these systems could function on a semi automatic basis that have biological or genetic memory components associated with them through the segmented consciousness awareness navigation system.

The attention vector of any individual specifically the geometrical direction that is pointed by the consciousness is powered by an energy source which is unique to any individual. specifically the origin of the geometric coordinate system that was created which could extend beyond one or two generation depending on the purpose of creation

The source or the origin serves as the energy source that drives the attention vector towards the velocity and direction of the attention vector which is navigated through the geometric axis system which functions by calculating relative distances of all relative movements in the current location to the next probable locations and the trajectories to reach the locations.

The origin of the coordinate system then provides the energy source for this location that goes fron one point to the next .

But since each origin and the geonetric coordinate system has a unique origin and source depending on the creation purpose .

Suppose if thee was a methord to temporary destabilize the source or the origin using technological or other methords , the biological components that have independent conciousness that function with various levels of awareness based on memory could be quantum entangled to another individuals geometric coordination system with its own origin along with the source of energy.

Thus another coordinates system and it's origin source of energy could be quantum entangled to another individuals biological movement metrics

This creates a copy of the other individuals motives or specfically family and territory tree intents into the target indidvuals conciousness . The life force is different because the origin of the intent and source of energy is different . This could be surgical procedure developed by intelligence agencies to create Covert

spies during ww2 .

It would be like one mind that controlled two bodies but the other body functions with a coordinated navigation system with the original mind almost like an AI copy that perfects does what is needed according to circumstances defined by the original mind using the procedure . The energy source for the life movement is however shatwd from the source.

(This would be non mechanized version of the borg using the unobserved quantum state principle)

10.2 The geometric copy of the consciousness

Suppose if there was a way the geometric coordinate system of any individual could be copied such that it could be used as and when necessary like a boundary condition for the perception function.

A individual is born at time t = 0 at a location " X "

As the individuals consciousness starts to grow by increasing its awareness it could do so with the following :

The consciousness starts with the establishment of the identify coordinate system axis . Then the directional axis and finally the energy source identification axis Z. Since every individual is diverted towards the source of the energy for its life movement.

As the conscious awareness of the individual grows , the individual could grow several more axis all perpendicular to the collective axis before it , this increases the number if dimensions with which the individual could observe and interact with the surroundings for its forward movement.

Therefore the the coordinate system itself could be copied as a template or a blueprint by conducting another procedure based on the same quantum entanglement procedure based on the unobserved quantum state procedure where the blueprint is assumed to be copied with attention energy dmfir a duration of time T which is assumed to be required for the procedure.

Once the procedure is completed , it could in theory be used by diverting attention towards the individual or the blueprint directly based on the creators association.

Suppose if consciousness states or explicitly geometric coordinate systems could exist in the subconscious information field of any location that has any sort of association with the individual, it could in theory be borrowed or assumed such that the perception of the individual particularly the boundary condition of his

observation of geometric metrics that the attention vector has associated with could be used.

Since in the geometric context, the life experiences of the individual is stored in the number of axis the individual has developed along with the number of variables that each axis records to identify and trace relative movement in the surroundings. Any specific function that an individual does from engineering to medicine could be correlated to the geometric movement of the individual under various circumstances in the surroundings. All responses and reactions could be mapped mapped geometrically. Thus allowing the blueprint of any individual could be extracted from the subconscious information field and used to navigate the movement vector field .

This would produce a variable movement instinct than the one the individual possesses.

11 Engineering Time-flow

Suppose at any location that is defined by " X " . Let there be " n " individuals in the locations who are in movement relative to each other . The relative movement could be defined as an interaction that had a starting point t = 0.

The end point point of the interaction would bot be dependent on the movement of the individuals but rather the intent of the interaction.

Assuming that every interaction starts with a purpose or an intent .

There could be two kinds of interactions :

1. Interactions that are defined by the duration T units where the interaction ends deterministically after the duration units . The movement in the location is expected to variable , the amount of energy for the interaction could either be fixed or variable.

2. Purpose based interactions where the movement in the location " X " is expected to be variable

The time duration of the interaction is also expected to be variable .

The energy for the interaction is also expected to be variable .

The only deterministic component would be the purpose with which the interaction could be started.

For these kinds of interactions , the movements in the locations would have be continually monitored where there is a large expecting of stochasticity in the movement.

Suppose if the purpose of the interaction is " Y ". Then the purpose Y could be met by the following sequence of movements.

Individual one has to start from A1 (beginning of the interaction) and rest at B 1

Individual two has to start from A2 (beginning of the interaction) and rest at B 2

....

There if all the n individuals end at locations B1,B2....Bn

Then the purpose could be assumed to met .

But if one of the individual i fails to reach destination Bi , the purpose is not fully met .

Thus the interaction could go indefinitely untill either the energy or the time that is available for the interaction runs out.

Since a purpose based interaction model requires the constant observation of the trajecteies that each individual takes , higher amount of energy is required to monitor such interactions and further more an external force Fi may need to be applied to each individual such that his trajectory will be redirected towards the expected Bi .

Suppose the energy for such interactions could be defined exclusively for the amount of time duration T units it takes to complete the interaction , the expected amount of time T to complete the interactions becomes important

This cpuld be because of the amount of energy that is directly proportional to the following variables :

number of Individuals (higher energy for more individuals)

Longer the trajectory (higher energy for higher navigation area)

Higher the movement drag (higher the potential energy required to overcome inertial forces)

Suppose if each individual "i" has " N " trajectories to get from his current location Ai to his target location Bi , then the higher the value of N , then higher number of computational possibilities for the trajectory for i .

Since there are " n " individuals, then There are a total number of " n * N " possibilities for the combined movement trajectories .

Since there could only be x % of movement trajectories that are possible to ensure that all points "i" end at their respective Bi .

The probability of x could be lower or higher depending on the geometrical configuration of the overall location X.

Thus the amount if energy that has to be directed towards each individual also depends on the overall probability correlated to the overall geometric structure of X.

Specifically the application of various external forces could have to applied at various stabilizing intersection points in the geometry to ensure each individual

is at the right junction at he right time to interact with the other individuals such that the right mini interaction occurs that result in the overall target trajectory

11.1 Visualizing the source of energy for such purpose based interactions

Suppose if the external energy for such interactions could be embedded in the flow of time itself then it could visualized as follows :

Suppose if each individual has a local subconscious information field that has a cloud of information around him at any time " t " , then the energy from his attention vector is being directed towards the various pieces of information . Specifically the trail of energy is mapped at any time " t " such that the individual is associated with all the locations that is correlated to the i formation from his local subconscious information formation field .

The relative locations of any individual's current location relative to the surrounding locations that are associated with locations of interested where the information as kind of energetic medium to those locations.

In any joint interaction , the local subconscious information field of each individual merges such that a cloud of interaction field us created with all the information associated based on all the information that each of the individuals attention vector is tied to through various locations

This creates a total set of locations " Z " that each individual could get to from his current location if he had access to all the location trajectories. However the exact location that each individual could likely prefers is the locations that is associated with his unique particular subconscious information field.

The navigation of these trajectories for each of these individuals could occur by the conscious instinct that creates his unique movement vector field for navigation in the location " X "

The movement vector field for each individual is then a set of directional instructions to go from from his current location state at time " t " to his target location state at the next instant of time " t + 1 " in discrete form .

In continuous form , the flow of directional information occurs from one instant to the next as a list of probable trajectories in the short, medium or long term .

In the continuous flow of time , any individual has a set of instincts that is

being guided by his consciousness attention vector that is aligned to his movement vector field that is correlating the information from his local subconscious information field to the overall global subconscious information field in the overall interaction of the location

Suppose if the flow of time (time dimension in geometric form) in any location could be engineered such that it could alter or deviate the movement vector field of all the individuals in the interaction such that the attention vector of consciousness receives directional information from. this altered field , the process could be accomplished by various sequence of steps .

Since the movement vector field is created for each individual by the attention vector of consciousness by integrating the local subconsciousness information field with overall interaction subconsciousness information field ,

Application of external force in the interaction at various sub locations could force the dissociation of the attention vector from the local subconscious information field to the global subconscious information field .

Thus will force the attention vector of consciousness to correlate locations that either not relevant or forced by the blocking off certain trajectories by information distortion in various mini interactions that is compounded into the the overall interaction

This forces the change in the movement vector field .

Suppose if one of locations that was naturally set at Bi , then by altering the attention of the individual the attention of the individual could in their be forced to the location Ci either by forcing the change in direction or by a setting up a distraction at Ci such that it has a higher response rate from the individual.

Thus the movement vector field changes from the original instincts that was the driving the individual from Ai to Bi to an externally engineered one to go from Ai to Ci

For complex situations , where purpose based engineering occurs since the variable T and energy could be extended indefinitely until the resources are available ,

The trajectory of he " n " individuals would have to be continually be monitored such that in any mini interaction that occurs in any sub location , the right trajectory is chosen such that the amount of time that it takes to reach the overall trajectory for each individual form Ai to Bi could be achieved. Thus the process of purpose based interaction engineering becomes a problem of time minimization for each individual to get form his current location Ai to his expected target location Bi.

The movement vector field of any individual could be visualized as a unique geometric coordinate system that has been created by the source location of the individual and the total amount of information that he could perceive with his local subconscious information filed and the overall interaction subconscious information field.

Since each individual uses the same geometric coordinate system the ability of each individual to correlate his location subconscious information field to the overall interaction field in the location field becomes a location identification problem of all the information available in the location " X " relative to the origin of his geometric coordinate system .

The measurement of the locations by any individual's attention vector occur by drawing perpendicular bisectors form his reference axis relative to his direction and attention axis and thus identifying the shortest distance to reach the target destination.

In theory the individual with the highest number if axis drawn perpendicular to various set if axis where each axis represents information change that could be observed with relative movement in the surroundings measured by the reference axis.

Engineering the movement vector field of any individual geometrically could occur by introducing an interference to his attention axis thus creating a distortion in the energy field in his local subconscious information field .

Thus the directional axis of the individuals geometric coordinate system is altered and consequently the reference axis of the measurement system estimates the minimum distance to the unintended location .

The function of the movement vector field for any individual could simply be defined by the number of directions any individual could take at any point in time which could be infinite in a void but is always finite in a geometric enclosed location such as " X "

If any individual's intents could be known at any location " X " and time " t " which could broadly categorized as survival , non survival or sexual instinct , and prior information about the individual could be known then specific triggers could be introduced to redirect the attention axis of the individual.

12 Defining Consciousness as a location awareness mechanism

Suppose if an individual A is born at time t = 0 and dies at time t = T and he could be assumed to have traveled to " n " locations where he spends a random amount of time " dt " before he dies.

During the T years of life , the individual's life could represented as the following Location - Time matrix ,

t = 0

Individual A is born at location "X0"

Individual A is assumed to be in the location " X0 " for a duration = dt0

The number of individuals interacting with individual A = N0

The number of possibilities for the next location = x_0

Where "x0" represents the total number of locations that is in the stored memory of all the individuals (N0 + 1) that could be the probable next trajectory for individual A. Suppose if individual A is assumed to the masculine in the location then he is assumed to have access to all the locations in the local subconsciousness information field of the location X0. Depending on the hierarchy of the individuals based on their conscious awareness , the amount of locations they have access to in the location X0 could be a subset of x0.

t= t + dt0

Individual A is born at location "X1"

Individual A is assumed to be in the location " X1 " for a duration = dt1

The number of individuals interacting with individual A = N1

The number of possibilities for the next location = x_1

.....

t = T - dtn

Individual A is born at location "Xn"

Individual A is assumed to be in the location " Xn " for a duration = dtn

The number of individuals interacting with individual A = Nn

The number of possibilities for the next location = 0 because he is assumed to die at t = T

Let the consciousness of individual A be defined as location storing mechanism where the total number of locations stored is defined by the location set

Set A = (x_1+x_2+...+ x_n-1)

Where the set A contains information regarding all the locations that the individual has been to including the the locations that he aspires to be , his aspirations for future locations etc. Every one of these locations has a state that is associated with it with respect to his intent in the location. If the location is stored in the memory of the individual then there is an intent associated with it that describes what his movement of observation of interaction would be in that location.

When the individual was alive, the individual could observe the locations in dynamic form in the dimension of time which is assumed to fueled by the kinetic energy originating from the observing masculines with their attention energy based on their expected target state of the location.

Suppose at the time of death , the individual's last thought was associated with a location in the set A then his attention vector could transfer his consciousness to that location. Since he has no physical body then his consciousness becomes pure awareness in the stillness. This implies he may not observe the location as a flow of time but rather as an image (a frozen four dimensional fragment of time) of that location that would allow his intent for the location. It could be assumed to be the exact moment or state in the location that could allow for the time flow movement for his intent. It could serve as a boundary condition for the location to observe his own life for that intent where his attention was driving his conscious awareness.

This means that depending on the number of observers of that exact state in the location , the number of variables that affect the simulated life movement process starting with the photographic four-dimensional image of life movement . If individual A is the only individual observing that state in the location then his attention energy could determine the exact movement of life that is occurring in the simulation of life which is aversion of his past self through various new situations.

If this process occurs then the conscious awareness of the individual could be two variations arising from the same source. For instance when the conscious awareness created the static four-dimensional image then this starts a new mode

of life movement that could be of the form :

t = 0

The conscious awareness creates a new state of one of the locations in Set A through a four-dimensional image that describes the initial boundary condition for the intended state of life movement.

Since the conscious awareness of individual A longer has a physical body to observe and interact with the image without creating a flow of time for the image to be extrapolated to , he has to create the flow of time from his attention energy . This process could be achieved by create a sequence of target state trajectories.

At t = 0

The conditions for the simulation of an indented life for individual A is created through the state and location where there could be "N1" individuals associated with the intent .

Individual A defines another location- state extrapolated four-dimensional image from the initial state image at t = 0 . This could be defined similar to a " what if " situation originating from initial state. If the extrapolated state could be defined as the next time of observation t = T1.

....

Individual A defines another location- state extrapolated four-dimensional image the image at time t = T2

.....

The defined extrapolated states location define his sequential observation of the simulated reality for observation.

The consciousness of individual A is therefore create states (photographic images) one after the other for the version of life that he intents to observe that are essentially sequential set of images one after the other.

Since the images that are created as extrapolated versions of the previous images are defined by location and state , the intervals of time that are defined by time t = T1,T2,.... may not be linear .

This is because the initiated image that is defined with the state location could be extrapolated backwards in which case it would be the extrapolated images of how the image came to be or it could be extrapolated forwards in which case

it would describe how another image could be created . Both directions of the image extrapolated could be observed could be observed.

The movement that is assumed to have occurred between the points of observation T = 0 , T1, etc could be defined as transition states. If the conscious awareness that created the images between the transition state then he could merge his conscious awareness with the version of himself that has the physical body that would be integrated into the movement vector field of the individual A who was created to observe and interact with the defined intent in the transition between images.

This creates a shared experience of the intent with a few variations within himself. This is because if the image was created with a state and location that is defined from his conscious awareness as an aspiration , then based on his awareness of his location set , the states of those locations and the N1 individuals that define the new simulated reality a reality is created that may not match his expected reality . This is because the movement vectors of each individuals are defined by regressing their movements based on their intents (geometric actions over time) that is stored in the local sub-conscious information field of individual A.

Therefore the experience of the transition between states includes deterministic and stochastic components for the movement.

Suppose if there are " N1 " individuals that are associated with the intent of individual A in the created image then their observing conscious awareness could be integrated into the simulated reality depending on whether they choose to observe the transition to the desired target states by Individual A.

The higher the number of observing consciousness in any simulated reality , the higher the amount of energy that it receives and consequently absorbs attention energy from other observing consciousness in various other simulated reality. These simulated realities could be sorted based on locations and could describe the various parallel realities or timelines in that location.

Therefore the underlying reality in any location is therefore the superposed simulations of simulated realities from conscious higher dimensional geometric entities and the energy to drive the transition state is provided by the total N number of individuals that are in the location whose time and attention is drained towards these realities until one of those realities absorbs all the available potential energy in the location.

If the indented transition location state that is absorbing the highest amount of energy is to drain the location and abandon it then the purpose of the entire simulation becomes pointless.

12.1 Trajectory plotting of the fifth dimensional awareness through their attention

Suppose if an individual A is born at time t = 0 and dies at time t = T and he could be assumed to have travelled to " n " locations where he spends a random amount of time " dt " before he dies.

During the T years of life , the individual's life could represented as the following Location - Time matrix ,

t = 0

Individual A is born at location "X0"

Individual A is assumed to be in the location " X0 " for a duration = dt0

The number of individuals interacting with individual A = N0

The number of possibilities for the next location = x_0

t= t + dt0

Individual A is born at location "X1"

Individual A is assumed to be in the location " X1 " for a duration = dt1

The number of individuals interacting with individual A = N1

The number of possibilities for the next location = x_1

.....

t = T - dtn

Individual A is born at location "Xn"

Individual A is assumed to be in the location " Xn " for a duration = dtn

The number of individuals interacting with individual A = Nn

The number of possibilities for the next location = 0 because he is assumed to die at t = T

Let the consciousness of individual A be defined as location storing mecha-

nism where the total number of locations stored is defined by the location set

Set A = (x_1+x_2+...+ x_n-1)

Where the set A contains information regarding all the locations that the individual has been to including the the locations that he aspires to be , his aspirations for future locations etc. Every one of these locations has a state that is associated with it with respect to his intent in the location. If the location is stored in the memory of the individual then there is an intent associated with it that describes what his movement of observation of interaction would be in that location.

12.1.1 Types of consciousness

Let there be two types of consciousness based on their ability to observe and interact in the locations.

Three dimension perspective - Experiencing time in continuous form where there is movement of three dimensional geometry in the time flow relative to the individual's current location.

The consciousness of the individual A when he was alive could be defined through his movement through locations where he spends an average amount of time " dt " units in each location. The intent of the individual A is defined through his action over a period of duration " dt ". The intent could then be defined as the following modes of geometric actions :

Observation

Interaction

Experience

The entire duration of the time " dt" is defined as the conscious experience of the location which the rate of change of geometry that occurs in continuous form implying that the experience cannot be stopped. It could be defined as the flow of time that is moving at a constant rate however the rate is defined by the observer of the time flow in the first person perspective. The first person perception is then defined as the continuous observation of the rate of change of geometry relative to the self without the ability to halt the time flow.

12.1.2 Fifth dimension perspective - Experiencing time in discrete form

The consciousness of individual A when no longer a physical body could be experienced in discrete form where the set A describes all the locations that the individual has in his memory . The conscious attention of the individual could switch between the locations and he could observe the location in discrete form as a three dimensional block that creates a kind of image of the exact state of the location that individual A has stored in the memory set A.

Particularly the set A has all the following information regarding all the locations specifically the location information that describe its state :

1. The outer external boundary of the location

2. The intent of individual A for which the location has been stored

3. The exact location of individual A relate of the external boundary of the location

4. The locations of all the objects and individuals relative to individual A's location in the external boundary.

Each location in the set A has the above details stored in the consciousness of individual A.

The experience of time could occur in the following format , the individual A could select any one of the above locations to observe

t = 0

The individual observes location x0 in discrete form with respect to intent of the location.

If the location of the individual was stored in his consciousness when the individual experienced life in continuous form (three dimensional perspective) , then the events that happened in the location could be defined as an intent that lasted for a duration " dt "

If the location and its state is accessed by individual A in the fifth dimensional perspective then the individual could create the location that may or not reflect the events that occurred in continuous form. The individual could reimagine or visualize the same location under different conditions such as having a different intent , different individuals (stored from various other locations) , different objects etc. and the discrete form could be created to experience in discrete form.

12.2 Continuity of the location

t = T1

The individual could further visualize the conditions of movement that leads to the exact image that was visualized at time t = 0 , for the discrete form of fifth dimensional perspective , this would the linear flow of observation. However if the events were to be experienced in continuous form by an observer , the flow of time would be experienced in continuous form in the reverse order of time flow relative to his surroundings. In such a scenario , the fifth dimensional perspective could observe time in the reverse order where as the third dimensional perspective of the individual who simulates the transition state from t = 0 to t = T would experience time in the forward direction parallel to the flow of time in the surroundings.

If the three dimensional perspective of the individual starts observation at birth in the forward direction of time , the fifth dimensional perspective or the observer who had explicitly created the fourth dimensional image and created an extrapolation backwards in time such the exact conditions for the third dimensional perspective to observe the exact location trajectories that converges to the created fourth dimensional image by the observer at an unknown time t = T

However the duration of time T units between t = 0 and t = T could be split into N discrete planes of time such that T = dt + dt +..... = N * dt and the two modes of consciousness could intersect at a point t = T_lim

The three dimensional perspective of individual A experiences life in continuous form and after a period of time = T_lim (usually 1/3 of the average lifespan 33 years) intersects with the fifth dimensional perspective or the observer who is observing his trajectory in discrete form backwards in time frame by frame at each " dt " where the lifespan of individual A would appear to be an four dimensional image frame by frame .

At which point the consciousness of the individual would merge with the observer or the fifth dimensional awareness that would enable the trajectory of the individual to reach its target location.

This could occur by the integrating the instincts of the individual's third dimensional perspective with the fifth dimension perspective that could have forecasting ability in the multiverse to ensure the target location of individual A is reached.

12.2.1 The backwards in time observation of the discrete fifth dimensional perspective

Suppose if the observer creates a four dimensional image at time t = T that is a location and a state defined . Let this be defined as the first observation n = 1

The observer then identifies a point discrete point in time t = T -1 that is an extrapolation of the image created at t = T

The observers then observes the number of individuals or observers (N1 = three dimensional observers and the fifth dimensional observers) of individual A . This determines the number of contradictory intents that prevent the image transition from T-1 to T.

The observers then calculates the number of possible trajectories that are possible to go from t = T - 1 to t = T in continuous form based on the intents of all the individuals interacting with individual A including individual A himself in the intersection locations between the time points T-1 to T.

Let " k1 " be the number of trajectories that are possible to go from T-1 to T in continuous form. (forward in time in continuous form) and K1 be the number of trajectories that would prevent the image transition from T-1 to T based on the N1 observers who would like to divert the trajectory of individual A.

If k1/K1 greater than 1 then the probability of the transition is high and if the k1/K1 less than 1 then the probability of the transition is low and if k1/K1 = 1 the transition between the states is equiprobable.

Similarly the analysis could be done by creating various discrete points of time such as T,T-1,T-2,....,t = 0 .

Suppose if there is an increasing number of contradictory intents from various individuals from one transition state to the next then the probability of each image reaching the next transition state becomes lower and lower .

This is because as the final transition state T-1 to T is reached , the number of observing individuals with contradictory intents would be maximum and the N1 would be maximum and k1 would be proportionally lower.

This means for the three dimensional perspective moving forward in time in continuous form the variables take the form as shown below :

k1,k2,.....kn - Ascending order which describes the number of trajectories or timelines that allow the successful transition to the final state T.

N1,N2,... Nn - Descending order which describes the number of individuals who observe and intercept the trajectories to prevent the successful transition to the final state T.

13 The geometric observers

Let individual A's timeline be defined by the following trajectory mechanics that is defined by the location-time matrix in the location X.

Let there be " K " individuals in the location " X "

Let there be an observer called observer Prime who is observing the boundary.

Let there be " K " individuals in the location " X "

13.1 Outside the Location boundary X

Let there be an observer called observer Prime who is observing the boundary.

The boundary of the location X is defined through the external geometric parameters by observer prime with the following conditions.

Let the observer label his location as the point " O ".

Let the observer then draw a perpendicular line to the point . This line forms the first axis " x ".

Let the observer then draw a perpendicular line to the axis " x " This line forms the second axis " y ".

Let the observer then draw a perpendicular line to both the axis " x " and " y " . This line forms the third axis " z ".

Let the observer then draw a perpendicular line to all three axis " x ",“ y " and " z". This line forms the third axis " t ".

. . . . . .

Let the observer then draw a perpendicular line to all (n-1) axis " x ",“ y " , "z",. . . ,(n-1) This line forms the nth axis " N ".

Since there be " K " individuals in the location " X " , let them all start the same process of drawing perpendicular axis with respect to their locations.

This means that there is one observer outside the location " X " with his own geometric coordinate system and growing planes of geometry . Where the value of N is the number of axis drawn in a sequential process of perpendicular axis

creation with increasing complexity. With each axis created , a new point of view is created which could be defined as a kind of external observation of all the axis before its creation.

13.2 The location boundary X

Suppose in the location X , For any random point P where one of the individual is located if the existence of the observer O outside the location "X" is not known then his geometric coordinate system could not be observable because he is not aware of it.

The point P then creates his own coordinate system , in the exact same manner . The way in which the coordinate system is constructed could be a deterministic function of the individuals that could be analogous to a generalised form of the geometric function of conciousness.

Suppose if the the point P is also unaware of the other (K-1) individuals within the location X , then he will not be aware of the other geometric coordinate systems that is being constructed by each of those (K-1) individuals.

Therefore independently there are K geometric coordinate systems within the location X and one geometric coordinate system out the location X.

At any point of observation from individual O , the dimensions of location X could be defined within the geometric coordinate system of the observer. This is because the observation of the location " X " could have occurred only by defining the boundary for the observation , in this case the pre-existence of the geometric cordinate system to observe the " K " individuals.

The " K " points that could be observed by the point O have no dimensions themselves but dimensionality only occurs if the observer identifies the location of each point by plotting a perpendicular line from his location to the point P being observed.

Then the observer at point O uses his geometric coordinate system to identify the relative location of the point P with respect to his location. This process could be done by drawing a perpendicular bisector to the location of the point P from one or more of its its axis " t " .

The distance between the location of the point O and the location of the point " P " mirrored on the " t " axis describes the relative distance between the observer and the point P.

However the observer at point O could continue to plot various locations of

point P if the interaction of the perpendicular bisector between the " t " axis of the observer and the point P.

This process then establishes a sequences of points " k " on the " t " axis of the observer through the " k " perpendicular bisectors being drawn.

The movement relationship between the observer and the point with each perpendicular bisector is given by the relative distance between the points .

Suppose if the observer is tracking all the " K " individuals with the same method , this would increase the complexity of observation specifically with the relative distances between all the permutations and combination of points in the boundary .

13.3 Tracking other observers

If the observer is tracking three points P,Q and R from the location O then ,The relative distances between O,P,Q and R must measured simulataniously in every permutation and combination possible to establish the deterministic pattern of movement being mapped by the observer.

Suppose if one of the " K " individuals within the location " X " are unable to observe the point " P " , but they are able to observe the points based on their movement trajectory plotting .

This means that if the point P started its own coordinate system with respect to its own location and during the process it is able to observe a random point Q . This could be understood with the assumption that as the number of axis grows for any individual point P , the volume of its observation space increases. For instance , if the point P had only one axis , then its observation could occur along only direction at a time. If there two axis drawn from the point P , then it has four modes of observation which could be called as quadrants and so on

The higher the number of axis , and each axis provides two directions then the number of possibilities variations to observe the point Q could increase substantially.

And since the point Q has the same geometric coordinate system with the exact same properties , the more quadrants that the point Q draws the more dimensional possibilities that it has for its next location. Since the coordinate system of each point is unique with respect to its point of origin. The point of origin in this context is the creation of the geometric coordinate system that defines the geometrical uniqueness of each coordinate system.

Since the points P and Q have the same state space with the exact same coordinate system used for movement referencing , the point P could only trace the point Q , if it is aware of the following metrics :

The exact origin of the location Q reflected on the coordinate system of the point P. The exact number of axis the point Q has drawn , this would allow for the point P to estimate the number of possible variations of geometric coordinates possible for the movement of the point Q.

The relationship between the location of the point Q relative to the location of the the point P could be established by drawing the perpendicular bisector from the axis of measurement of the point Q and mirroring the point on the axis of measurement of point P. This provides the relative distance between the locations . However if the number of axis that the point Q has drawn starting from the location of its axis creation exceeds the number of axis created by the point P , then the exact location of the Q could not be mirrored on the measuring axis of the point P because the measuring axis has lower dimensions than the measuring axis of the point Q. The coordinate that would be mirrored in the geometric coordinate state space of the point P would be a partial fragmented reflection where the missing dimensions of the point's location could not be observed because the perpendicular axis to cover the additional dimensional combinations would be missing. As the number of dimensions increases with each perpendicular axis to the existing axes , the number of observable dimensions also increases by several times. Thus increasing the number of states spaces available for commutation.

14 Geometric Current moment

A change of Perception from third perspective to first perspective

Suppose if an individual's is located in a location " X "

Let there be N sub-locations in the location X , such as X1,X2,X3,. . . .Xn

Where each sub-location has a defined area for movement such that the total area will add up to the total area of " X ".

Suppose an individual is located outside the location X , and decides to enter the location X.

The intent of the individual determines which one of the " n " target sub-location in the location X is his target destination. Let the target destination for the individual be X7 .

Let the individual have access to three sub-lob locations to enter the target destination X such as X1,X2 and X3.

The individual determines the sub-location to enter the location X based on the law of the law of minimum action . This is determined by the calculating the distance to travel from each entry sub-location to the target sub-location and determines which trajectory requires the least amount of time and energy to reach the target sub-location destination .

Let each sub-location have a purpose for its creation where a set of intents will serve as the interaction key to enter the sub-location.

Therefore the state of the location X that the individual tries to reach could be defined as matching the individual's intent to the appropriate sub-location .

Suppose if each sub-location has a set of " K " intents that define its purpose , then "k" out K intents could be defined as true intent and (K-k) intents could be defined as projected intent .

The projected intent for any location could be described as the projection of information that is specifically designed to attract individuals into the location such that individuals would match their true intents to the projected intent and enter various sub-locations based on their individual intent.

Since all locations are associated with energy , the movement of individuals either adds or removes potential energy from the location . Under this context the deception could be described as the following:

True intent - Drain energy from the individual to the location

Projected intent - Provide energy to the individual from the location

Thus the projected intent process enables free movement of " N " individuals at any given duration of time T units where a total amount of net energy of Energy E units is absorbed into the location.

Where certain individuals could provide energy to various individuals based on their intent while most individuals would provide energy in various sub-locations. Therefore the overall energy that is absorbed into the location will be a positive energy of E units. The energy could be absorbed at various sub-locations through out the location. The energy is then stored and used by the masculines of each sub-locations and then directed towards the sub-location where the masculine prime of the location will divert the energy to either :

Maintain the state (A balance of True intents and projected intents) , thus the overall movement frequency remains the same and the energetic state of the location is kept stable.

Degrade the state (A higher proportion of projected intents than true intents) , thus the overall movement frequency reduces and the energetic state of the location degrades.

Upgrade the state (A higher proportion of True intents than projected intents) , thus the overall movement frequency increases and the energetic state of the location upgrades.

14.1 The mechanism of projected intents

Suppose each sub-location also has K intents then :

Number of true intents - k

Number of projected intents - (K-k)

Suppose an individual enters the sub-location by match is true intent to one the projected intents (K-k)

Then the expected outcome from the individual is that the individual spends T units of time as an overall interaction where he interacts with a random number of " Q " individuals and deduces the key for his next target destination which could either be one of the sub-locations in the locations or any other location outside X.

14.2 Application of deception

Since the individual is not consciously aware about the projected intent , his total amount of time spent in the sub-location would be (T+D) units where D units of time is create the illusion of projected intents by introducing the keys (locations) that may or not be relevant for the true intent of the individual. The additional component of time D units is then used to navigate other sub-locations or exploring irrelevant information .

Therefore the D units of time become crucial for the sub-location to drain the required amount of energy under the projected intent context.

14.3 Differential equations and locations

If there are N individuals then there a set of N differential equations that describe the movement in the location. The collective movement is then defined by the set of boundary conditions to solve the equations where each boundary condition describes how much time any individual spends an average amount of time at each sub-locations or other individuals.

In mathematical terms the equations describe the iterative set of locations that each point could choose for its next trajectory in an enclosed boundary space relative to the movements of the other points trajectory. This combined interaction is then , a location hopping mechanism that occurs from point to the next while in the location. The choice of the next location to hop towards is defined by the boundary conditions.

The set of fixed boundary conditions under the context could be defined by the awareness of all the location possibilities by each individual.

Therefore the total amount of locations that are available in each location is therefore the complete set of locations that is stored in the subconscious information field of each individual.

Suppose if any point is within the interaction field of the local subconscious awareness field of another point or location , then the point could have access to have the locations that are accessible in the local subconscious information field of the other point or location.

The modeling of this process becomes stochastic as each point trajectory of N individuals interacts from one sub location to another after spending an amount

of time dt in each sub location. This process could be a function of the interaction time specifically the amount of the time that each point spends in each sub location. This could be a function of all the sub-locations that the point is interacting with . This is because if any point in any location is interaction is interacting with all the surrounding sub locations then , all the locations that are accessible to the surrounding locations or points could depend on observing their movement trajectory .

By observing the movement trajectory of he surrounding locations the most common chosen exit locations that occurs from each location could be determined which could be a function of conscious awareness and the observation time of the individual.

15 Timeline Mapping

Let individual A's timeline be defined by the following trajectory mechanics that is defined by the location-time matrix.

Let there be " n " individuals in the location " X "

Let there be a location " X " defined by the boundary through external geometric parameters.

Let there be N sub - locations defined within the location " X " that could be defined as various grids through out the territory.

15.1 The timeline

At time t = o

The individual is located at sub location X1

The duration of time spent in the sub-location X1 - dt1 units

The individuals interacting with A - Individuals X,Y,Z... etc

The amount of time spent with individual X_1 - dtX_1

The amount of time spent with individual Y_1 - dtY_1

The amount of time spent with individual Z_1 - dtZ_1

At time t = t+dt1

The individual is located at sub location X2

The duration of time spent in the sub-location X2-dt2 units,

The amount of time spent with individual X_2 - dtX_2

The amount of time spent with individual Y_2 - dtY_2

The amount of time spent with individual Z_2 - dtZ_2

.....

At time t = t + dtn

The individual is located at sub location Xn

The duration of time spent in the sub-location Xn - dtn units

The amount of time spent with individual X_n - dtX_n

The amount of time spent with individual Y_n - dtY_n

The amount of time spent with individual Z_n - dtZ_n

15.2 Factoring the overall population

Suppose if there are "n" such timelines from each individual in the location, then , the joint interaction matrix that occurs for each interaction defined by the series could be as follows :

At location X1

The interactions are sorted by time as follows :

In the duration of time [0,dt1]

The number of individuals interacting is defined by the set containing the information - k1

In the duration of time [t,t+dt2]

The number of individuals interacting is defined by the set containing the information - k2

. . . .

In the duration of time [t, t + dtn]

The number of individuals interacting is defined by the set contain the information - kn

15.3 Factorization of the timeline

For any individual A chosen , the above factorization could be made such that his time distribution could be sorted through continuity such as :

Individual A interacts with individual X for a total duration of Tx units and the interaction occurs in (j / n) locations .

n - The total number of sub-locations

j - the number of sub-locations out of n where Individual A interacts with a random individual X

Where the fraction j/n could be a proportion of the total sub-locations.

15.4 Correlating an individual's timeline with other timelines

Thus the distribution could be sorted in descending order of the proportion and the timeline of the individual could be traced through correlations with the other timelines. This should establish a relationship of any individual's timeline with respect to the other timelines with the location-time matrix.

Suppose for any individual A the above distribution could be sorted as the following format per location along his trajectory such:

Individual A's timeline trajectory could be rewritten as based on the interaction metrics based on the descending order of frequency such as :

Individual A in interactions with individual X in the most of locations and consequently the maximum amount of time spent together (ex. j/n = 0.9 More than ninety percent)

Individual A in interactions with individual Y in the most of locations and consequently the maximum amount of time spent together (ex. j/n = 0.8 More than eighty percent)

.....

Individual A in interactions with individual Z in the most of locations and consequently the maximum amount of time spent together (ex. j/n = 0.05 Less than ten percent)

Individual A in interactions with random individuals Q unique or random.

15.4.1 Sorting the above interactions

Suppose if the above interactions could be sorted as two categories such as :

Mid-Long term - Shared time and location is the highest

Short term - Shared time and locations is the lowest from one to five.

15.5 The Strategy

The life strategy of any individual could either be stochastic or deterninistic as most individuals make their strategic choices for location - time along the trajectory in the forward direction of time.

The relationship between any location and the individuals is expressed as follows.

Let the masculine of any location is the owner of the location who designs the interaction keys for location. Specifically the movement startgeies in that location which consequently decides the individuals entering and leaving the locations at various time intervals as a feedback loop .

Therefore the feedback loop is as follows :

The individuals choose the location based on external observation of the location and enters , however the internal observation of the location determines the true intent of the location.

The outside observation of any location could be expressed as the projected intent while the internal observation determines the true intent.

The difference between the two is determined by a metric called unobserved time.

While the external observation of movement in the location could be described as projected intent. This is where the individuals are aware that their movement is being observed.

On the other hand , the movement inside the location includes a time distribution called unobserved time. The movement in unobserved time is not visible to the individuals outside the location but it is visible to the individuals in the location.

The introduction of deception for unobserved time inside the location. Suppose the movement of the individuals inside the location could be altered using perception engineering where the perception of movement of a certain duration "D" units of time could be altered such that the true intent is not perceived by a set of individuals thus rather projected intent is perceived . This creates an illusion for the internal observers. While the reason for the deception could

be several , the true intent could always be correlated to the exchange of energy.

The deception process requires time and energy set up by the masculines thus creating another packet of time called unobserved time even for the internal observers. The time is usually volunteered by the collaborators and energy is usually volunteered by the unsuspecting individuals.

16 The geometric observation of energy

Let there be a location " x " that is defined by a set of geometric boundaries. The location " x " is assumed to be located in an unknown geometric configuration .

Let there be " N " individuals in the location " x " . Each of the individuals are assumed to be in movement in the location " x " . The movement is defined by the lifeforce that is driving the movement.

The purpose of the movement could be summarised as the following :

1. Survival needs

2. Non survival needs

3. Reproductive needs

The life-force is assumed to be provided from the territory itself and is correlated to the needs above in one way shape or form. Therefore there is continuity of information, energy and mass transfer between the location and the individuals.

Let there be an observer at a location O at an unknown location outside the boundary that is enclosing the location "x " .

Assuming the observer could observe the life-force movement of the N individuals in the location " x " , he could model the perception of the individuals through geometric metrics. It as also assumed that the individuals could not observe the observer and thus his location would be unknown.

The perception of the individuals has to be assumed and thus the observer uses the geometric dimensions to determines their movements strategy . Therefore he assumes the dimensions they could observe and interact with based on prolonged observation of each individuals between each other and the territory.

Since there is conservation of mass, energy and information between the territory and the individuals , he assumes that if the individual interacts with any of dimensions that has a correlation with geometry , then he could determine their perception.
Let number of dimensions that the observer could observe in the location " x " be defined as " D " .

Each dimension could describe any variations of the following :

16.1 Energy

1. The observer could identify which sub-locations within the location " x " such as x1,x2... , the individuals absorbing energy.

2. Transfer of energy between the individuals and the territory after the energy has been absorbed.

3. Identify individuals that have a larger capacity for energy storage , higher rate of energy rejuvenation , higher rate of energy dispersion etc. The converse could also be identified where individuals with a lower capacity for energy storage , lower rate of energy dispersion etc.

16.1.1 Correlation of the above information with geometry

Since the observer could not have the first hand observation of the individual's perception , he could isolate the sub -locations where the energy transfer is occurring and correlate it to interaction in the sub-location.

This process could be achieved by the geometric analysis of each sub-location. This process could be observed by the shift in the relative locations of each individual with respect to the observer.

Suppose the observer cannot determine the movement correlation without a frame of reference ,the observer could use a frame of reference or axis. He first establishes a frame of reference.

1. The observer identifies a center (approximately the mid point of the energy activity that he is observing) and calls it origin.

2. The observer then plots a single axis " X " passing through the center and tries to correlate movement using the axis as reference. He could do this by drawing a perpendicular bisector from his location to the axis and marks the point as " t1 "

In this context , the " t1 " represents the location of observation . The observer could then simultaneously draw perpendicular bisectors from the locations of the " N " individuals on the axis .

3. If the observers repeats the experiment over and over again " k " times , then he would have " k " sequential points of reference to trace the movement of the N individuals such as :

Observer locations : t1 t2 t3 ... tk

individual one : x11 x12 x13 .... x1k

.....

individual N : xN1 xN2 xN3 .... xNk

The observer then checks the energy inflow and outflow with the following format :

Energy flow from all the possible coordinates defined as a matrix above. The observers location is included because the application of the perpendicular bisector to observe the relative movement of the " N " individuals implies transfer of energy or information must occur and therefore the energy from the attention of the observer is being conserved in one way shape or form in the location.

The above location information matrix has N rows and k columns and therefore the flow of energy originating from any location and ending at any location could be defined by the number of ways a line could be drawn from one location to another connecting through the surrounding cells only. The assumption of continuity implies that energy, information could flow through a medium only and in this context , the medium are the individuals that are in movement.

Therefore if the location of individual one changes from x11 to x12 , then the total amount of energy between the locations has to be conserved.

Let individual one have E1 units of energy at his location x11

Le individual two have E2 units of energy at his location x12

Then the total amount of energy spent for the movement must be dE = (E2-E1) units , where dE must be the proportion of his free energy.

Any energy source E has two components , usable U_free and unusable energy U_fixed .

The assumption is that an individual has a limited amount of free energy at any location , if the free energy from the individual is extracted , then the individual becomes static or his trajectory stops. This is because the movement of the individual stops.

If there was an objective to absorb the free energy of an individual U_free , his movement could be intercepted at any location such as x12 . The process could be established by creating movement drag with an external energy source F_free for the individual such that the individual's free energy interacts with the location x12 to create friction for his movement until his movement stops .

The process only works if the external force from the energy source F_free is higher than the free energy U_free available to the individual at the location x12.

If however the free energy F_free does not fail to stop the movement of the individual at x12 , then the energy is absorbed by the individual in the location x12.

Since the state of any location is directly proportional to the individual that is the location , the interaction of energy between any individual and the location that he is currently is could be a unique signature .

This means that the energy stored in any location with respect to any individual could have a unique signature that defines the state and consequently the frequency of the individual.

Suppose if the external energy source F_free stops the trajectory of individual one then this specific state energy E12 that is causing the movement of the individual reduces thus altering the state/frequency of the location .

If however the external energy source F_free does not stop the trajectory of individual one then this specific state energy E12 that is causing the movement of the individual will either absorb, mirror or redirect it using the laws on continuity described above.

This implies that the excess energy U_free of the individual increases and thus could be used to direct it to from the location X12 to another destination through continuity such as X13,X14,....X1k however the energy is not transferred from the same state or frequency that is originates from.

This is because if the individual who has directed the external energy could be individual "X0t2". Where X0 is the observer and he could have directed the energy from the same location but from a different state that is explicitly defined by his energetic state in the location which is E02 .

If the external energy that is originating from the observer in the location X02 , then the energy is defined at the energetic state E02 and its corresponding frequency.

If individual one is located in the same location but at a different state X12 , then his energy could be redirected back to the source but at a different state . Therefore the energy received F_free is decomposed into two components :

F_free = F_work + F_new

Where F_work is used to change the state of the energy from EO2 which is

the originating state to the new state E12 which is the state of individual one.

Therefore F_new = (F_free - F_work) is redirected back to the energy channels of the observer X02. Since the energy is neither accessible nor observable for the sender of the energy , it is diverted into the new state of the same location that is correlated with individual one's location X12 where it becomes a possible future trajectory of the individual

17 Tracing the energy trail of the masculine

Let an individual's life be defined as one state that is defined by the collection of intersection of all the location that the individual has traveled to through out his lifetime.

The individual's lifetime is defined as a sequence of information given by the set of information shown below.

t= t + dt0

Individual A is born at location "X1"

Individual A is assumed to be in the location " X1 " for a duration = dt1

The number of individuals interacting with individual A = N1

The number of possibilities for the next location = x_1

.....

t= t + dt1

Individual A is at location "X2"

Individual A is assumed to be in the location " X2 " for a duration = dt2

The number of individuals interacting with individual A = N2

The number of possibilities for the next location = x_2

.....

t = T - dtn

Individual A is at location "Xn"

Individual A is assumed to be in the location " Xn " for a duration = dtn

The number of individuals interacting with individual A = Nn

The number of possibilities for the next location = 0 because he is assumed to die at t = T

The defined set is then summarized as :

Location set where the individual A has been to throughout the course of his life P = (X1,X2,...Xn)

The individual's that individual A has interacted with through out the duration of his life Q = (N1,N2,...,Nn)

Where the individuals could be assumed to independent in each location. However the individual is likely to interact with the same individuals in some of these locations . Therefore let N be the total number of unique individuals , individual A interacts with where M = N1 U (non repeating union) N1 U (non repeating union) .....Nn

The state of the individual is then correlated to the set P and Q which define in sequential order the location he has visited along with each individual that he has interacted with. Then the state of individual A is defined by the time series :

Without the location

The individual's life state could be described in terms of the interaction duration with the M individuals such as :

Individual A interacts with individual one for a duration of t_one units

Individual A interacts with individual two for a duration of t_two units

...

Individual A interacts with individual m for a duration of t_m units

Therefore the state of the individual could be described by the time series T = (t_one + t_two +...+ t_m) units
Where the each of the time variable is determined by the attention variable of individual A in the location where the interaction is occuring. Suppose if the state of the individual could then be defined through the transition of states from one location to another such as :

Current state

X1

After a duration of dt1 units of time , the target state is entered.

Target State

X2

After a duration of dt2 units of time , the new target state is entered.

Suppose if the state of individual A is correlated to the set of M individuals then , the duration of time dt that is spent in each location X is assumed to be for the following :

1. Individual A spends a duration of dt units in each location X to find all the correlated locations " x " to the state of the location X.

2. Individual A then determines the direction of energy flow from all the correlated locations to the location X.

3. If energy is being or absorbed diverted from or to location X to one or more of the locations " x " , then the number of channels for the energy flow and consequently the amount of energy that is being diverted or absorbed could be determines.

4. If the net energy is being absorbed into the location X , then the masculine of intersecting locations each location that is sharing the state of energy flow is assumed to be in the location X.

5. If the net energy is being diverted out of the location X , then the exact location where the maximum energy is being diverted to could be assumed to be the location of the highest ranking masculine that is correlated to the location " X ".

17.1 The State of the individual A in the location X

Suppose the attention vector of the individual could be described in terms of the amount of time that is spent in each location , then in terms of the observation of all the locations " x " could occur in the following format.

t= t + dt0

Individual A is born at location "X1"

Individual A is assumed to be in the location " X1 " for a duration = dt1

The number of individuals interacting with individual A = N1

The number of possibilities for the next location = x_1

.....

t= t + dt1

Individual A is at location "X2"

Individual A is assumed to be in the location " X2 " for a duration = dt2

The number of individuals interacting with individual A = N2

The number of possibilities for the next location = x_2

The amount of attention energy that is available for the individual could be measured in time .

This is because if the amount of attention that an individual could exert in his surroundings could be defined as a constant where the attention vector of consciousness could establish a energetic connection to one or more of the locations.

Suppose if individual A observers the locations X3,X5 and X4 for the longest duration of time out of all the possible " x_2 " locations , then it could be assumed that the next destination for individual A could be the maximum amount of attention that has gone to these locations measured in time.

At the location X2 , the individual's duration of time that is spent is defined as " dt2 " units. If there were several locations in the next possible location set for individual A then , the next location in the trajectory for individual A is likely to be the location which consumed the attention of the individual through his time.

Therefore the time distribution of individual A in location X is split as :

Individual A spent dt2 units of time in location X

There are N2 individuals in location X

Therefore the time distribution is therefore split as :

Time spent with individual one = dt_1 units

Time spent with individual two = dt2_2 units

Time spent with individual two = dt2_3 units

....

Time spent with individual N2 = dt2_n2 units

where dt2 = dt2_1 + dt2_2 +...+ dt2_n2

If dt2_3 is the maximum amount of time spent by individual A with individual three then the origin location of individual three is likely to be the next location for individual A.

18 Relative Linearity of Time

Suppose in an enclosed boundary or location " X " where there is an observer .

In the enclosed boundary there are " n " individuals whose movements are being tracked by the linearity of the observers timeline.

Suppose if each individual in the location or the boundary of X , is plotting his own own trajectory from various sub locations x11 , x12 ....

Lets Suppose if there are " N " sub-locations in the location of X .

Therefore the entire area is divided into " N " sublocations each with a defined area that sum up to the larger area X .

Suppose each individual is traversing through the location through by plotting various trajectories from one sub location to the next .

Let each sub location have " K " sub-intents that defined for its existence.

Where k - True intents

(K - k) - projected intents

Let each individual have an intent " i " that has to match one of the " K " intents otherwise it would not be possible to enter the sub-location.

Therefore the trajectory if any individual " x " based on the duration of his stay in each location is given by :

xiN_lim

Where " i " is the intent that he uses to enter the sub location N

Since there are " K " possibilities intents to enter the state there could be K values that the variable " i " could take .

If there are a total number if " N " sub-locations in the location X , there could only be N_lim sub-locations that he could access for his next trajectory point based on his current location and state.

Therefore for the individual from one sub-location to the next there could be (N_lim * K) variations of his next trajectory.

The trajectory of the individual could be represented based on his first perspective observation of time as :

t = 0 , The individual " x " enters a new location at sub-location X1 based on his intent

X1_i_ N_lim

Where i is the choice of the intent that he makes out if K possibilities available to enter the location .

N_lim is the number of sub-locations that he could continue his trajectory based on his choice of the sub-location X1.

This implies that based the continuity of information that allows a trajectory pathway to go from X1 to any other sub location Xi based on his choice of intent that he made to enter X1.

The individual observes the sub-location X1 for a duration of dt1 units of time. From his first perspective, time takes a linear continuous form that is represented as flow that cannot be halted because the state of observation takes the form of a continuous linear flow to observer rate of change of geometry in the surroundings.

Depending on the scale and dimension of observation explicitly defined by the attention vector before he enters the location and the flow would not end until the desired observation set by the attention vector is complete before entering the location.

Under the context, the location is a function of the individual's consciousness by his choice of intent " i " to experience as a flow (rate if geometry change) in the location X1. The flow would only stop when the number of trajectories or locations to enter the next sub-location Xi defined by the variable N_lim reduces to zero.

Therefore the location trajectory is not limited to the geometrical dimension of the location X or the various sub-locations X1,X2,....

But rather a interaction of the geometric configuration of each sub-location and the individual's consciousness that is determining the intent of the individual towards the geometric configuration specifically the rate of change of geometry that he wishes to observe and the interaction that he could make to the flow of change such that the trajectory of the rate of change of geometry that could be altered according to his intent .

This could either occur through the completion of the intent or simply the movement drag in the location is too high to prevent further movement. This could occur as an application of external force or through the internal forces

that are acting in the location to create drag for the intent movement that is occurring.

Since each individual " x " spends an amount of time " dt " in each location depending on his attention vector (defines his attachment to the scale and dimension in the surroundings) and the intent correlation that he has for the surrounding geometry , the total lifespan of each individual takes a unique form defined by the trajectory given by :

t = 0

X1_3_6

This means that the individual has entered the sub location 1 , with intent number (i = 3 out of K = 4 available for location 1) and there are 6 locations (X2,X3,X4,X5) where he could continue his trajectory towards for his timeline pathway given by T = dt1 + dt2 + dt3 +...

Where dt = Dt + DT

Where

DT - time used for projected intent

Dt - time used for true intent

In terms of the relationship between the geometric location (sub-location) and the conscious intent , this means that :

An individual may enter location X1 under the projected intent i = 3 but his true intent maybe i = 5.

The engineered deception occurs through time where Dt units of time is used for the true intent of i = 5 where the individual interacts with the surroundings to alter the rate of change of geometry according to the scale and dimension of observation of his attention vector.

The projected intent is required because a certain amount of time has to used to create the illusion of the continuity of projected intent to satisfy the justification for the existence of the individual in the location X.

18.1 Changing the perception from first perspective to the third perspective

18.1.1 The Observer linearity of Time

Let there be an observer outside the location X ,

The observer is aware of the " n " individuals in the locations and they

The observer is using his measurement axis to plot a perpendicular bisector at each point " t " to the sub-locations of each individual relative to his current location.

The linearity for the perception of time fir the observer outside of the location X changes based on his mode of measurement specifically the scale and dimension of observation.

The rate of change of geometry that the attention vector of the observer is making is the change of relative positions of each of the " n " individual with his point of measurement given by t1,t2,.... etc

Since the observer has a state that is defined by his intent in his current location , the measurement of the movement of the n individuals that he is making also has a state reference with respect to the observer.

Specifically if the observer starts to measure the relative movement of each of the n individual from state to state that has three components :

X - The base geometric coordinates that he used for the next state

" i " - The state of the individual that describes his attention vector during the movement specifically the metrics that provides continuity to go from one state to the next .

"N_lim " - The number that describes the probability for the continuity for this trajectory .

However the movement that is being tracked by the observer based on his linearity of movement observation could be described as x_i_X

For example,
x_(i =4)_X2 , x_(i = 4)_X6 ,....

where

x is the identified individual that is being tracked at the time of observation

by the external observer

X is the reference dimensional and scale of the location where the individual is located with respect to his own current reference dimensional and scale of observation of the location.

Where i represents the attention vector of the individual specifically the trial of information that his conscious intent is plotting the trajectory with respect to the geometry .

The above trajectory could only plotted through the conscious intent of the observer himself (i) that describe the exact points that he chooses to plot the perpendicular bisectors at various locations on his reference axis towards the " n " individuals.

Therefore the overall observer also has a state through which that he uses to plot the trajectories fir any individual such as :

Let the conscious intent of the observer be " i " which includes the acting of sorting trajectories of all the " n " individuals with respect to his state or conscious intent .

At ti1

x_(i)_Xn

At ti2

x_(i)_Xn

....

Each individual x is using his concious intent " i " to navigate the location Xn at each point if observation by the observer are ti1,ti2,....

However the observer is assumed to have the sane concious intent " i " to make the observation for the " n " individuals.

Suppose if the individual has " K " possible intents for the observation then he could have " K * N_lim " probable trajectories for observing each individual at each point of observation t.

Since there could be further (N_lim * K) probable trajectories that each individual could take based on his observation i side the location X , then total number of probable trajectories for observation at each point t for the individual could be defined by :

(K_observer * N_lim_observer) * (K_individual * N_lim_individual)

18.2 Altering the State of Observation

Suppose if an observer from outside the location " X " is observing the " n " individuals in the location X with respect to one of his conscious intents " i ". Let the observer have " K " intents in total.

Let the observer be quantum entangled with one of the individuals in the location " X " .

This allows the observer to have two modes of observation :

The third perspective where his linearity of time is defined by his own state (location) of geometric observation with respect to the relative movement of " n " individuals. This mode of observation would be in discrete form where the locations of each individuals could be observed instant by instant.

The first perspective where his linearity of time defined by the individuals state (location) with respect to the relative movement of " n -1 " individuals in a continuous state of movement . This mode of observation would not allow for the instantaneous observation of the locations of the surrounding individuals. This could also imply that the third perspective observation of the outside observer could not be available to accesss.

18.2.1 The Change of States

Let the observer make an observation at time ti1 which is a geometric point on his reference axis for movement . The measurement of the location of the entangled individual is made to be x_i_X

Since the individuals are entangled the state of both individuals are aligned to be the same conscious intent " i ".

Under the condition the location of the external observer is assumed to be at ti1

The location of the internal observer (the entangled individual) is assumed at x_i_X

Suppose for the internal observer,

His trajectory could be simplified as follows in discrete time steps :

At t = 0

Location - X1

Time spent in Location - dt1

Number of correlated individuals - " P1 " (These are the individuals who are connected to the individual (internal observer) in one way shape or form. Specifically in the context of energy where the individual has either absorbed or transferred energy to the " P1" individuals . This exchange of energy quantum entangles the trajectories of the " P1 " individuals to the internal observer.

At t = t + dt1

Location - X2

Time spent in Location - dt 2

Number of correlated individuals - P2

. . . ..

Let the driving conscious intent of the internal observer be " i " which could be represented as the purpose of life movement.

Let the external observer change one of his intents at current location X2 such that his intent is changed from " i " to " i_new " starting from location X1.

18.2.2 The correlation to Energy

Suppose this change could be represented through an imbalance the overall energy that could occur in the trajectory starting from the location X1.

Specifically if E1 units of energy was transferred from the internal observer to the " P1" individuals in the original state " i " , then the new state chosen " i_new " by the external observer could be such that " E1" amounts was transferred from the " P1" individuals to the internal observer in the location X1.

Since the individual is already in location X2 , the change in the entangled trajectories of the internal observer and " P1 " individuals cannot occur.

However the imbalance in energy that has occurred without the change in movement trajectories must be resolved in the current state or location.

Since the trajectories of " P1 " individuals and the internal observer remains the same , the forward trajectory should be affected . This is because each trajectory contains the potential and kinetic energy for its forward movement that is updated at every location in the interaction time.

Since the imbalance in energy should directly affect the stored potential energy of all the individuals since the kinetic energy of the individual could not be affected directly in the current X1.

Since potential energy is mainly sued to control the directional trajectories of each individual timeline to counter inertial forces,directional changes in trajectories,energy for rotational observation for plotting trajectories, navigating movement drag etc , the amount of energy access for the all the individuals interacting with the internal observer would change.

Specifically the stored energy of individuals P1, P2 would be altered and thus reducing the continuous awareness of the individuals for plotting movement trajectories along with the reduced ability to control the trajectory or locations for their movements.

18.2.3 The mechanics of the state change

Since the trajectories of the "P1" individuals and the internal observer are unchanged , the changes that result in the reduction of potential energy of the P1 individuals outside their scale and dimension of observation. Specifically outside the scope of their attention vector from each of their interactions such that the shift in the energetic in-balances shoulder resolved either in the current location " X2 " or any trajectory locations that follow "X3"," X4",...

Conversely the additional energy that the internal observer has gained will either be accessible in the current location "X3","X4" etc .

Since the observing individual has the higher amount of potential energy as a consequence , he could have the conscious awareness and control to extract it through various means or locations through the mastery of information continuity specifically regarding his location and the relative locations of the " P " individuals.

18.2.4 The unobserved time and the geometric back-flow effect

The change that has occurred in conservation of energy must occur outside the observed time of the P individuals such that the change in geometry that has

to provide continuity between the locations X1 and X2 such the resulting final change will be entangled to the " P " individuals to either divert , extract or reduce their overall potential energy or make it intert. This process is called geometric smoothing and occurs as a result of the conversation of momentum and energy that occurs through the trajectory connected with linearity of the time-flow and consequently flow of information through the geometry.

This could be considered a kind of a time ripple effect that flows backwards in time till the point of origin specifically the location and the point of time that had enabled the state of state of state from " i " to " i_new " to occur.

The geometric smoothing could occur through various individuals that the " P " individuals that have come in contact with through out the trajectory from the point of change.